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| Nota di contenuto | Preface; Contents; Introduction; 1. Vectors and Matrices; 1.1 Introduction; 1.2 Vector Inner Product; 1.3 Vector Cross Products and Skew Symmetric Matrix Algebra; 2. Coordinate Transformation between Orthonormal Frames; 2.1 Introduction; 2.2 Direction Cosine Matrices; 2.3 The Direction Cosine Matrix is a Unitary Matrix; 2.4 The Direction Cosine Matrix is a Transformation Matrix; 2.5 DCM Fixed Axis; 2.6 The Rotation Matrix; 2.7 Inner and Outer Transformation Matrices; 2.8 The Quaternion; 3. Forms of the Transformation Matrix; 3.1 Introduction; 3.2 Simple Frame Rotations; 3.3 Euler Angles 3.4 Rotation Vector 3.5 Quaternion; 3.6 Simple Quaternions; 3.7 Conversion between Forms; 3.7.1 Conversion between DCM and Euler; 3.7.2 Conversion between DCM and Quaternion; 3.7.3 Conversion between Euler Angles and Quaternion; 3.8 Dynamics of the Transformation Matrix; 3.8.1 DCM Differential Equation; 3.8.2 Quaternion Differential Equation; 3.8.3 Rotation Vector Differential Equation; 3.8.4 Euler Angles Differential Equation; 4. Earth and |

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7.6 Altitude (Descend/Climb) Rate; 7.7 Air Speed; 7.8 Indicated Air
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Azimuth Navigation; 8.3 Prospective of the Wander Azimuth Approach;
8.4 Polar Circle Navigation Algorithm; 8.5 Alternative Polar Circle
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Rate Gyro Threshold Selection; 11. GPS Aided Inertial System; 11.1
Introduction; 11.2 Navigation Frame Error Equation; 11.2.1 Craft Rate
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11.2.3 Position Errors

Sommario/riassunto

The emerging technology of very inexpensive inertial sensors is available for navigation as never before. The book lays the analytical foundation for understanding and implementing the navigation equations. It starts by demystifying the central theme of the frame rotation using such algorithms as the quaternions, the rotation vector and the Euler angles. After developing navigation equations, the book introduces the computational issues and discusses the physical aspects that are tied to implementing these equations. The book then explains alignment techniques. Introduction to Modern Navigation
