

Contents

Series Preface	xiii
Glossary	xv
1 Introduction	1
1.1 Background	1
1.2 Overview	2
1.3 Customs and Conventions	6
References	6
2 Coordinate Systems	7
2.1 Background	7
2.2 The Coordinate Systems	7
2.2.1 <i>The inertial reference frame, F_I</i>	7
2.2.2 <i>The earth-centered reference frame, F_{EC}</i>	8
2.2.3 <i>The earth-fixed reference frame, F_E</i>	8
2.2.4 <i>The local-horizontal reference frame, F_H</i>	8
2.2.5 <i>Body-fixed reference frames, F_B</i>	10
2.2.6 <i>Wind-axis system, F_W</i>	12
2.2.7 <i>Atmospheric reference frame</i>	12
2.3 Vector Notation	13
2.4 Customs and Conventions	14
2.4.1 <i>Latitude and longitude</i>	14
2.4.2 <i>Body axes</i>	14
2.4.3 <i>'The' body-axis system</i>	14
2.4.4 <i>Aerodynamic angles</i>	15
Problems	16
References	16
3 Coordinate System Transformations	17
3.1 Problem Statement	17
3.2 Transformations	18
3.2.1 <i>Definitions</i>	18
3.2.2 <i>Direction cosines</i>	18

3.2.3	<i>Euler angles</i>	21
3.2.4	<i>Euler parameters</i>	25
3.3	Transformations of Systems of Equations	26
3.4	Customs and Conventions	27
3.4.1	<i>Names of Euler angles</i>	27
3.4.2	<i>Principal values of Euler angles</i>	27
	Problems	27
	Reference	29
4	Rotating Coordinate Systems	31
4.1	General	31
4.2	Direction Cosines	34
4.3	Euler Angles	34
4.4	Euler Parameters	36
4.5	Customs and Conventions	38
4.5.1	<i>Angular velocity components</i>	38
	Problems	38
5	Inertial Accelerations	43
5.1	General	43
5.2	Inertial Acceleration of a Point	43
5.2.1	<i>Arbitrary moving reference frame</i>	43
5.2.2	<i>Earth-centered moving reference frame</i>	46
5.2.3	<i>Earth-fixed moving reference frame</i>	46
5.3	Inertial Acceleration of a Mass	47
5.3.1	<i>Linear acceleration</i>	48
5.3.2	<i>Rotational acceleration</i>	49
5.4	States	53
5.5	Customs and Conventions	53
5.5.1	<i>Linear velocity components</i>	53
5.5.2	<i>Angular velocity components</i>	54
5.5.3	<i>Forces</i>	54
5.5.4	<i>Moments</i>	56
5.5.5	<i>Groupings</i>	56
	Problems	57
6	Forces and Moments	59
6.1	General	59
6.1.1	<i>Assumptions</i>	59
6.1.2	<i>State variables</i>	60
6.1.3	<i>State rates</i>	60
6.1.4	<i>Flight controls</i>	60
6.1.5	<i>Independent variables</i>	62
6.2	Non-Dimensionalization	62
6.3	Non-Dimensional Coefficient Dependencies	63

6.3.1	<i>General</i>	63
6.3.2	<i>Altitude dependencies</i>	64
6.3.3	<i>Velocity dependencies</i>	64
6.3.4	<i>Angle-of-attack dependencies</i>	64
6.3.5	<i>Sideslip dependencies</i>	66
6.3.6	<i>Angular velocity dependencies</i>	68
6.3.7	<i>Control dependencies</i>	69
6.3.8	<i>Summary of dependencies</i>	70
6.4	The Linear Assumption	71
6.5	Tabular Data	71
6.6	Customs and Conventions	72
	Problems	73
7	Equations of Motion	75
7.1	General	75
7.2	Body-Axis Equations	75
7.2.1	<i>Body-axis force equations</i>	75
7.2.2	<i>Body-axis moment equations</i>	76
7.2.3	<i>Body-axis orientation equations (kinematic equations)</i>	77
7.2.4	<i>Body-axis navigation equations</i>	77
7.3	Wind-Axis Equations	78
7.3.1	<i>Wind-axis force equations</i>	78
7.3.2	<i>Wind-axis orientation equations (kinematic equations)</i>	80
7.3.3	<i>Wind-axis navigation equations</i>	81
7.4	Steady-State Solutions	81
7.4.1	<i>General</i>	81
7.4.2	<i>Special cases</i>	83
7.4.3	<i>The trim problem</i>	88
	Problems	89
	Reference	91
8	Linearization	93
8.1	General	93
8.2	Taylor Series	94
8.3	Nonlinear Ordinary Differential Equations	95
8.4	Systems of Equations	95
8.5	Examples	97
8.5.1	<i>General</i>	97
8.5.2	<i>A kinematic equation</i>	99
8.5.3	<i>A moment equation</i>	100
8.5.4	<i>A force equation</i>	103
8.6	Customs and Conventions	105
8.6.1	<i>Omission of Δ</i>	105
8.6.2	<i>Dimensional derivatives</i>	105
8.6.3	<i>Added mass</i>	105

8.7	The Linear Equations	106
8.7.1	<i>Linear equations</i>	106
8.7.2	<i>Matrix forms of the linear equations</i>	108
Problems		111
References		112
9	Solutions to the Linear Equations	113
9.1	Scalar Equations	113
9.2	Matrix Equations	114
9.3	Initial Condition Response	115
9.3.1	<i>Modal analysis</i>	115
9.4	Mode Sensitivity and Approximations	120
9.4.1	<i>Mode sensitivity</i>	120
9.4.2	<i>Approximations</i>	123
9.5	Forced Response	124
9.5.1	<i>Transfer functions</i>	124
9.5.2	<i>Steady-state response</i>	125
Problems		125
10	Aircraft Flight Dynamics	127
10.1	Example: Longitudinal Dynamics	127
10.1.1	<i>System matrices</i>	127
10.1.2	<i>State transition matrix and eigenvalues</i>	127
10.1.3	<i>Eigenvector analysis</i>	129
10.1.4	<i>Longitudinal mode sensitivity and approximations</i>	132
10.1.5	<i>Forced response</i>	137
10.2	Example: Lateral–Directional Dynamics	140
10.2.1	<i>System matrices</i>	140
10.2.2	<i>State transition matrix and eigenvalues</i>	140
10.2.3	<i>Eigenvector analysis</i>	142
10.2.4	<i>Lateral–directional mode sensitivity and approximations</i>	144
10.2.5	<i>Forced response</i>	148
Problems		149
References		150
11	Flying Qualities	151
11.1	General	151
11.1.1	<i>Method</i>	152
11.1.2	<i>Specifications and standards</i>	155
11.2	MIL-F-8785C Requirements	156
11.2.1	<i>General</i>	156
11.2.2	<i>Longitudinal flying qualities</i>	157
11.2.3	<i>Lateral–directional flying qualities</i>	158
Problems		166
References		166

12	Automatic Flight Control	169
12.1	Simple Feedback Systems	170
12.1.1	<i>First-order systems</i>	170
12.1.2	<i>Second-order systems</i>	172
12.1.3	<i>A general representation</i>	177
12.2	Example Feedback Control Applications	178
12.2.1	<i>Roll mode</i>	178
12.2.2	<i>Short-period mode</i>	184
12.2.3	<i>Phugoid</i>	188
12.2.4	<i>Coupled roll–spiral oscillation</i>	198
	Problems	206
	References	207
13	Trends in Automatic Flight Control	209
13.1	Overview	209
13.2	Dynamic Inversion	210
13.2.1	<i>The controlled equations</i>	212
13.2.2	<i>The kinematic equations</i>	215
13.2.3	<i>The complementary equations</i>	221
13.3	Control Allocation	224
13.3.1	<i>Background</i>	224
13.3.2	<i>Problem statement</i>	225
13.3.3	<i>Optimality</i>	231
13.3.4	<i>Sub-optimal solutions</i>	232
13.3.5	<i>Optimal solutions</i>	235
13.3.6	<i>Near-optimal solutions</i>	241
	Problems	243
	References	244
A	Example Aircraft	247
	Reference	253
B	Linearization	255
B.1	Derivation of Frequently Used Derivatives	255
B.2	Non-dimensionalization of the Rolling Moment Equation	257
B.3	Body Axis Z-Force and Thrust Derivatives	258
B.4	Non-dimensionalization of the Z-Force Equation	260
C	Derivation of Euler Parameters	263
D	Fedeeva's Algorithm	269
	Reference	272
E	MATLAB® Commands Used in the Text	273
E.1	Using MATLAB®	273
E.2	Eigenvalues and Eigenvectors	274

E.3	State-Space Representation	274
E.4	Transfer Function Representation	275
E.5	Root Locus	277
E.6	MATLAB® Functions (m-files)	277
<i>E.6.1</i>	<i>Example aircraft</i>	278
<i>E.6.2</i>	<i>Mode sensitivity matrix</i>	278
<i>E.6.3</i>	<i>Cut-and-try root locus gains</i>	278
E.7	Miscellaneous Applications and Notes	280
<i>E.7.1</i>	<i>Matrices</i>	280
<i>E.7.2</i>	<i>Commands used to create Figures 10.2 and 10.3</i>	281
Index		283