Geographic coordinates

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1 Introduction

The objective of this report is record all the features that an aircraft must have.

2 Techniques

Prefabricated parts PFP /premanufactured parts PMP
Instead of creating the same parts again and again, design the components and make them easily modifiable. for example, combine 2 parts to create a third one, which is useful in an other application. Then add them to the system in the assembly Example : threads : try the smallest possible size, for example M3 to M20.
Test them with small parts and check the tolerances. The next step is to prepare small parts ready to be added to system parts. The final step is the merge the bodies.
table

TABLE 1 – Holes and threaded holes

Screw	Threaded hole diameter	Bore Hole (clearance)
M3	2.8	3.2
4	35	144
5	45	300

Clearance To fix two part together, a clearance is needed. When two parts must be assembled together, a clearance of 0.1mm is enough. Then use the glue to fix the assembly.

TABLE 2 – Nonlinear Model Results

Case	Method#1	Method#2	Method#3
1	50	837	970
2	47	877	230
3	31	25	415
4	35	144	2356
5	45	300	556

$$Length_{lattitude}(\phi) = 111132.92 - 559.82 \cdot cos(2 \cdot \phi) + 1.175 * cos(4 \cdot \phi) - 0.0023 \cdot cos(6 \cdot \phi) = ...[m/degree] \quad (1)$$

1 degree longitude at latitude phi

$$Length_{longitude}(\phi) = 111412.84 - 93.5 \cdot cos(3 \cdot \phi) + 0.118 \cdot cos(5 \cdot \phi) = ...[m/degree] \quad (2)$$

3 Schéma cinématique

3.1 Vecteurs positions

origine : centre de rotation verticale se trouvant sous les pâles principales.

position des pâles principales (pp) : vecteur verticale

position de l'hélice arrière : vecteur allant de l'origine vers l'hélice (h) arrière.

4 Angular momentum

4.1 Formula

$$\vec{L} = \vec{OA} \otimes \vec{P} = \vec{r} \otimes \vec{P} = \vec{r} \otimes m \cdot \vec{v} = \vec{I} \otimes \vec{\omega} \tag{3}$$

$\vec{L}$: Angular Momentum $[kg \cdot \frac{m^2}{s}]$
$\vec{OA}$ and r : position of the mass $[m]$ according to a referance
$\vec{P}$: linear momentum $[kg \cdot \frac{m}{s}]$ [1]
$\vec{v}$: velocity $[\frac{m}{s}]$ I : moment of inertia $[m^2 \cdot kg \cdot]$
ω : angular speed $[\frac{rad}{s}]$
Torque :

$$M = \frac{d\vec{L}}{dt} = \frac{d(\vec{I} \otimes \vec{\omega})}{dt} \tag{4}$$

if we consider a particule of mass m, $\vec{r}$ is the position of the center of mass. If it is a solid object, L is first computed according to the axis of rotation of the object :

$$\vec{L}_{ar} = \vec{I}_{ar} \otimes \vec{\omega}_{ar} \tag{5}$$

To compute the angular moment according to an other axis of rotation (new referance), we use the Huygens-Steiner theorem (or the Parallel axis theorem) :

$$\vec{L}_0 = \vec{I}_0 \otimes \vec{\omega}_{cm} \tag{6}$$

$$\vec{I}_0 = \vec{I}_{ar} + m \cdot d^2 \tag{7}$$

with d the distance between the axis of rotation of the object and the new referance.

4.2 Condition of stability

Main rotor(s) :

$$\vec{L}_{mr} = \vec{r}_{mr} \otimes m_{mr} \cdot \vec{v_{mr}} = \vec{I_{mr}} \otimes \vec{\omega_{mr}} \tag{8}$$

Rear rotor :

$$\vec{L}_{rr} = \vec{r}_{rr} \otimes m_{rr} \cdot \vec{v_{rr}} = \vec{I_r r} \otimes \vec{\omega_{rr}} \tag{9}$$

assurer la stabilité lors du vol : les moments cinétiques doivent s'annuler. (poser la formule et résoudre)

$$\vec{L_{mr}} = \vec{L_{rr}} \tag{10}$$

or
The generated torque is compensated :

$$\sum \vec{M_{mr}} = \sum \vec{M_{rr}} \tag{11}$$

find a relation between ω_{mr} and ω_{rr} -> determine the transmission ratio

1. $\vec{L}$ is perpendicular to both $\vec{P}$ and $\vec{r}$

4.3 Pivots à droite et à gauche

pour tourner à gauche ou doite, on ne doit plus satisfaire la condition de stabilité. le pilote utiliser le pédalier pour accélérer/ralentir l'hélice arrière. ainsi les moments cinétiques ne sont plus égaux.

calculer l'effet de rotation sur l'hélicoptère si l'hélice est accélérée/ralentie de 10,20,30,.. %. mettre un tableau. calculer la vitesse de rotation dans ces cas-là.

$$\begin{bmatrix} 0 \\ 0 \\ l_1 \end{bmatrix}_{R_1} \quad \vec{AB}_{R_2} = \begin{bmatrix} 0 \\ l_2 \\ 0 \end{bmatrix}_{R_2} \quad \vec{BC}_{R_3} = \begin{bmatrix} l_3 \\ 0 \\ 0 \end{bmatrix}_{R_3} \quad \vec{CD}_{R_4} = \begin{bmatrix} 0 \\ 0 \\ -l_4 \end{bmatrix}_{R_4} \tag{12}$$

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$$\begin{aligned} \vec{OE}_R = {} & \vec{OA}_R + \vec{AB}_R + \vec{BB}_{1R} + \vec{B_1C}_{1R} + \vec{C_1C}_R \\ & + \vec{CC}_{2R} + \vec{C_2D}_R + \vec{DD}_{1R} + \vec{D_1E}_R \end{aligned} \tag{13}$$

$$\begin{aligned} \vec{OF}_R = {} & \vec{OA}_R + \vec{AB}_R + \vec{BB}_{1R} + \vec{B_1C}_{1R} + \vec{C_1C}_R \\ & + \vec{CC}_{2R} + \vec{C_2D}_R + \vec{DD}_{1R} + \vec{D_1E}_R + \vec{EF}_R \end{aligned} \tag{14}$$

$$\begin{aligned} \vec{OG}_R = {} & \vec{OA}_R + \vec{AB}_R + \vec{BB}_{1R} + \vec{B_1C}_{1R} + \vec{C_1C}_R + \vec{CC}_{2R} \\ & + \vec{C_2D}_R + \vec{DD}_{1R} + \vec{D_1E}_R + \vec{EF}_R + \vec{FF}_{3R} + \vec{F_3G}_R \end{aligned} \tag{15}$$

$$\begin{aligned} \vec{OH}_R = {} & \vec{OA}_R + \vec{AB}_R + \vec{BB}_{1R} + \vec{B_1C}_{1R} + \vec{C_1C}_R + \vec{CC}_{2R} + \vec{C_2D}_R \\ & + \vec{DD}_{1R} + \vec{D_1E}_R + \vec{EF}_R + \vec{FF}_{3R} + \vec{F_3G}_R + \vec{GH}_R \end{aligned} \tag{16}$$

5 Conclusion