

OrientationModel

5.3

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Chapter 1

Module Index

1.1 Modules

Here is a list of all modules:

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Chapter 2

Namespace Index

2.1 Namespace List

Here is a list of all namespaces with brief descriptions:

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Chapter 3

Data Structure Index

3.1 Data Structures

Here are the data structures with brief descriptions:

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jeod::Orientation	Specifies the orientation of one reference frame with respect to another	17
jeod::OrientationMessages	Declares messages associated with the orientation model	40

Chapter 4

File Index

4.1 File List

Here is a list of all files with brief descriptions:

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orientation.hh	Define the Orientation class	45
orientation_messages.cc	Implement the class OrientationMessages	45
orientation_messages.hh	Define the class OrientationMessages, the class that specifies the message IDs used in the orientation model	46

Chapter 5

Module Documentation

5.1 Models

Modules

- [Utils](#)

5.1.1 Detailed Description

5.2 Utils

Modules

- [Orientation](#)

5.2.1 Detailed Description

5.3 Orientation

Files

- file [orientation.hh](#)
Define the Orientation class.
- file [orientation_messages.hh](#)
Define the class OrientationMessages, the class that specifies the message IDs used in the orientation model.
- file [eigen_rotation.cc](#)
Define Orientation methods related to computing single axis rotations.
- file [euler_angles.cc](#)
Define Orientation methods related to computing Euler angles.
- file [orientation.cc](#)
Define methods for the NewOrientation class.
- file [orientation_messages.cc](#)
Implement the class OrientationMessages.

Namespaces

- [jeod](#)
Namespace jeod.

5.3.1 Detailed Description

Chapter 6

Namespace Documentation

6.1 jeod Namespace Reference

Namespace jeod.

Data Structures

- struct [EulerInfo](#)
Contains data needed to construct a transformation matrix given a sequence of Euler angles and to extract a sequence of Euler angles from a matrix.
- class [Orientation](#)
Specifies the orientation of one reference frame with respect to another.
- class [OrientationMessages](#)
Declares messages associated with the orientation model.

Variables

- static const [EulerInfo](#) [Euler_info](#) [12]
Contains twelve [EulerInfo](#) objects, one per each of the JEOD Euler sequences.

6.1.1 Detailed Description

Namespace jeod.

6.1.2 Variable Documentation

6.1.2.1 Euler_info

```
const EulerInfo jeod::Euler_info[12] [static]
```

Initial value:

```
= {
    {{0, 1, 2}, 0, 2, true, true},
    {{0, 2, 1}, 0, 1, false, true},
    {{1, 2, 0}, 1, 0, true, true},
    {{1, 0, 2}, 1, 2, false, true},
    {{2, 0, 1}, 2, 1, true, true},
    {{2, 1, 0}, 2, 0, false, true},
    {{0, 1, 0}, 2, 2, true, false},
    {{0, 2, 0}, 1, 1, false, false},
    {{1, 2, 1}, 0, 0, true, false},
    {{1, 0, 1}, 2, 2, false, false},
    {{2, 0, 2}, 1, 1, true, false},
    {{2, 1, 2}, 0, 0, false, false}
}
```

Contains twelve [EulerInfo](#) objects, one per each of the JEOD Euler sequences.

The elements are arranged per the values of the [Orientation::EulerSequence](#) enumeration items.

Definition at line 96 of file euler_angles.cc.

Referenced by `jeod::Orientation::compute_euler_angles_from_matrix()`, `jeod::Orientation::compute_matrix_from_euler_angles()`, and `jeod::Orientation::compute_quaternion_from_euler_angles()`.

Chapter 7

Data Structure Documentation

7.1 jeod::EulerInfo Struct Reference

Contains data needed to construct a transformation matrix given a sequence of Euler angles and to extract a sequence of Euler angles from a matrix.

Data Fields

- unsigned int [indices](#) [3]
The axes about which the rotations are performed in the order in which the rotations are performed, with X=0, Y=1, Z=2.
- unsigned int [alternate_x](#)
The initial element of the sequence for aerodynamics sequences, but the index of the omitted axis for astronomical sequences.
- unsigned int [alternate_z](#)
The final element of the sequence for aerodynamics sequences, but the index of the omitted axis for astronomical sequences.
- bool [is_even_permutation](#)
Indicates whether the 3-axis rotation sequence generated by replacing the final element of the sequence with the one axis not specified by the first two elements of the sequence is an even (true) permutation or odd permutation (false) of XYZ.
- bool [is_aerodynamics_sequence](#)
True if the sequence is an aerodynamics sequence such as XYZ; false for an astronomical sequence such as ZXZ.

7.1.1 Detailed Description

Contains data needed to construct a transformation matrix given a sequence of Euler angles and to extract a sequence of Euler angles from a matrix.

See [Orientation::compute_euler_angles_from_matrix](#) for details.

Definition at line 50 of file `euler_angles.cc`.

7.1.2 Field Documentation

7.1.2.1 `alternate_x`

```
unsigned int jeod::EulerInfo::alternate_x
```

The initial element of the sequence for aerodynamics sequences, but the index of the omitted axis for astronomical sequences.

For example, the omitted axis in a ZXZ sequence is `Y=1.trick_units(-)`

Definition at line 64 of file `euler_angles.cc`.

Referenced by `jeod::Orientation::compute_euler_angles_from_matrix()`.

7.1.2.2 `alternate_z`

```
unsigned int jeod::EulerInfo::alternate_z
```

The final element of the sequence for aerodynamics sequences, but the index of the omitted axis for astronomical sequences.

`trick_units(-)`

Definition at line 70 of file `euler_angles.cc`.

Referenced by `jeod::Orientation::compute_euler_angles_from_matrix()`.

7.1.2.3 `indices`

```
unsigned int jeod::EulerInfo::indices[3]
```

The axes about which the rotations are performed in the order in which the rotations are performed, with `X=0`, `Y=1`, `Z=2`.

For example, an XYZ or roll pitch yaw sequence is `{0,1,2}` while a ZXZ sequence is `{2,0,2}.trick_units(-)`

Definition at line 57 of file `euler_angles.cc`.

Referenced by `jeod::Orientation::compute_euler_angles_from_matrix()`, `jeod::Orientation::compute_matrix_from_euler_angles()`, and `jeod::Orientation::compute_quaternion_from_euler_angles()`.

7.1.2.4 `is_aerodynamics_sequence`

```
bool jeod::EulerInfo::is_aerodynamics_sequence
```

True if the sequence is an aerodynamics sequence such as XYZ; false for an astronomical sequence such as ZXZ.

`trick_units(-)`

Definition at line 88 of file `euler_angles.cc`.

Referenced by `jeod::Orientation::compute_euler_angles_from_matrix()`.

7.1.2.5 is_even_permutation

```
bool jeod::EulerInfo::is_even_permutation
```

Indicates whether the 3-axis rotation sequence generated by replacing the final element of the sequence with the one axis not specified by the first two elements of the sequence is an even (true) permutation or odd permutation (false) of XYZ.

The alternative 3-axis sequence is identical to the original sequence in the case of aerodynamics sequences. The astronomical ZXZ sequence becomes ZXY via this replacement rule. Since ZXY is an even permutation of XYZ, the is_even_permutation member for a ZXZ sequence is true.trick_units(-)

Definition at line 82 of file euler_angles.cc.

Referenced by jeod::Orientation::compute_euler_angles_from_matrix().

The documentation for this struct was generated from the following file:

- [euler_angles.cc](#)

7.2 jeod::Orientation Class Reference

Specifies the orientation of one reference frame with respect to another.

```
#include <orientation.hh>
```

Public Types

- enum [DataSource](#) {
[InputNone](#) = -1, [InputMatrix](#) = 0, [InputQuaternion](#) = 1, [InputEigenRotation](#) = 2,
[InputEulerRotation](#) = 3 }

Specifies which representation has been input by the user.

- enum [EulerSequence](#) {
[NoSequence](#) = -1, [EulerXYZ](#) = 0, [EulerXZY](#) = 1, [EulerYZX](#) = 2,
[EulerYXZ](#) = 3, [EulerZXY](#) = 4, [EulerZYX](#) = 5, [EulerYXY](#) = 6,
[EulerXZX](#) = 7, [EulerYZY](#) = 8, [EulerYXY](#) = 9, [EulerZXZ](#) = 10,
[EulerZYZ](#) = 11, [Roll_Pitch_Yaw](#) = 0, [Roll_Yaw_Pitch](#) = 1, [Pitch_Yaw_Roll](#) = 2,
[Pitch_Roll_Yaw](#) = 3, [Yaw_Roll_Pitch](#) = 4, [Yaw_Pitch_Roll](#) = 5, [RollPitchYaw](#) = 0,
[RollYawPitch](#) = 1, [PitchYawRoll](#) = 2, [PitchRollYaw](#) = 3, [YawRollPitch](#) = 4,
[YawPitchRoll](#) = 5 }

Identifies which type of Euler sequence has been specified.

Public Member Functions

- [Orientation](#) ()=default
- virtual [~Orientation](#) ()=default
- [Orientation](#) (const double trans_in[3][3])
Construct an [Orientation](#) instance from a transformation matrix.
- [Orientation](#) (const Quaternion &quat_in)
Construct an [Orientation](#) instance from a Quaternion.
- [Orientation](#) (double eigen_angle_in, const double [eigen_axis](#)[3])
Construct an [Orientation](#) instance from an eigen rotation.
- [Orientation](#) ([EulerSequence](#) sequence_in, const double angles_in[3])
Construct an [Orientation](#) instance from an Euler rotation.
- virtual void [reset](#) ()
Forget that we have any data.
- virtual void [compute_transform](#) ()
Compute the transformation matrix from the source.
- virtual void [compute_quaternion](#) ()
Compute the left transformation quaternion from the source.
- virtual void [compute_eigen_rotation](#) ()
Compute the eigen rotation from the source.
- virtual void [compute_euler_angles](#) ()
Compute the eigen rotation from the source.
- virtual void [compute_all_products](#) ()
Compute all represented charts on SO3 from the specified source.
- virtual void [compute_transformation_and_quaternion](#) ()
Compute the transformation matrix and quaternion.
- void [set_quaternion](#) (const Quaternion &quat)
Reset the instance with a new quaternion.
- void [get_quaternion](#) (Quaternion &quat)
Accessor for the left transformation quaternion.
- void [set_transform](#) (const double trans[3][3])
Reset the instance with a new matrix.
- void [get_transform](#) (double trans[3][3])
Accessor for the transformation matrix.
- void [set_eigen_rotation](#) (double [eigen_angle](#), const double [eigen_axis](#)[3])
Reset the instance with a new eigen rotation.
- void [get_eigen_rotation](#) (double *[eigen_angle](#), double [eigen_axis](#)[3])
Accessor for the eigen rotation.
- void [set_euler_angles](#) ([EulerSequence](#) sequence, const double angles[3])
Reset the instance with a new Euler rotation.
- void [set_euler_angles](#) (const double angles[3])
Reset the instance with a new Euler rotation.
- void [get_euler_angles](#) ([EulerSequence](#) *sequence, double angles[3])
Accessor for the Euler angles.
- void [get_euler_angles](#) (double angles[3])
Accessor for the Euler angles.
- [EulerSequence](#) [get_euler_sequence](#) ()
Accessor for the Euler sequence data member.
- void [set_euler_sequence](#) ([EulerSequence](#) sequence)
Set the euler_sequence data member.
- void [clear_euler_sequence](#) ()
Reset the euler_sequence data member.

Static Public Member Functions

- static void `compute_quaternion_from_euler_angles` (`EulerSequence` sequence, const double angles[3], Quaternion &quat)
Compute the left transformation quaternion from the Euler sequence.
- static void `compute_matrix_from_euler_angles` (`EulerSequence` sequence, const double angles[3], double trans[3][3])
Compute the transformation matrix from the Euler sequence.
- static void `compute_euler_angles_from_matrix` (const double trans[3][3], `EulerSequence` sequence, double angles[3])
Extract an Euler sequence from the transformation matrix.
- static void `compute_matrix_from_eigen_rotation` (double eigen_angle, const double eigen_axis[3], double trans[3][3])
Compute the transformation matrix from the eigen rotation.
- static void `compute_eigen_rotation_from_matrix` (const double trans[3][3], double *eigen_angle, double eigen_axis[3])
Compute the eigen rotation from the transformation matrix.

Data Fields

- `DataSource` data_source {`InputMatrix`}
Orientation data source – specifies whether the user has provided as input an Euler rotation, a transformation matrix, or a left transformation quaternion.
- `EulerSequence` euler_sequence {`NoSequence`}
The Euler rotation sequence corresponding to euler_angles.
- double euler_angles [3] {}
Euler angles corresponding to rotation sequence euler_sequence.
- double trans [3][3] { { 1.0, 0.0, 0.0 }, { 0.0, 1.0, 0.0 }, { 0.0, 0.0, 1.0 } }
Transformation matrix.
- Quaternion quat
Left transformation unit quaternion.
- double eigen_angle {}
Single axis rotation angle.
- double eigen_axis [3] {}
Single axis rotation axis unit vector.

Protected Member Functions

- void `mark_input_as_available` ()
Mark the item specified by the data_source as available.
- void `compute_quaternion_from_euler_angles` ()
Compute the left transformation quaternion that corresponds to the provided Euler rotation sequence.
- void `compute_matrix_from_euler_angles` ()
Compute the transformation matrix that corresponds to the provided Euler rotation sequence.
- void `compute_euler_angles_from_matrix` ()
Compute an Euler rotation sequence that corresponds to the provided transformation matrix.
- void `compute_matrix_from_eigen_rotation` ()
Compute the transformation matrix that corresponds to the provided eigen rotation.
- void `compute_eigen_rotation_from_matrix` ()
Compute a eigen rotation that corresponds to the provided transformation matrix.

Protected Attributes

- bool `have_transformation_` {}
True if transformation matrix has been set/computed.
- bool `have_quaternion_` {}
True if quaternion has been set/computed.
- bool `have_eigen_rotation_` {}
True if eigen rotation has been set/computed.
- bool `have_euler_angles_` {}
True if an Euler rotation has been set/computed.

Static Protected Attributes

- static double `gimbal_lock_threshold` = 1e-13
Threshold for detecting gimbal lock in `compute_euler_angles_from_matrix`.

Friends

- class `InputProcessor`
- void `init_attrjeod_Orientation` ()

7.2.1 Detailed Description

Specifies the orientation of one reference frame with respect to another.

There are many competing charts on the rotation group. This class provides means for representing rotations as Euler rotations, transformation matrices, left transformation quaternions, and eigen rotations. The class also provides mechanisms for converting these representations into the alternative representations.

Definition at line 83 of file `orientation.hh`.

7.2.2 Member Enumeration Documentation

7.2.2.1 DataSource

```
enum jeod::Orientation::DataSource
```

Specifies which representation has been input by the user.

Enumerator

<code>InputNone</code>	No source specified.
<code>InputMatrix</code>	Transformation matrices supplied by user.
<code>InputQuaternion</code>	Quaternions supplied by user.
<code>InputEigenRotation</code>	Single axis rotation supplied by user.
<code>InputEulerRotation</code>	Euler sequence and angles supplied by user.

Definition at line 90 of file orientation.hh.

7.2.2.2 EulerSequence

```
enum jeod::Orientation::EulerSequence
```

Identifies which type of Euler sequence has been specified.

Enumerator

NoSequence	No sequence specified.
EulerXYZ	XYX sequence (roll pitch yaw)
EulerXZY	XZY sequence (roll yaw pitch)
EulerYZX	YZX sequence (pitch yaw roll)
EulerYXZ	YXZ sequence (pitch roll yaw)
EulerZXY	ZXY sequence (yaw roll pitch)
EulerZYX	ZYX sequence (yaw pitch roll)
EulerXYX	XYX sequence.
EulerXZX	XZX sequence.
EulerYZY	YZY sequence.
EulerYXY	YXY sequence.
EulerZXZ	The canonical ZXZ Euler sequence.
EulerZYZ	ZYZ sequence.
Roll_Pitch_Yaw	XYX sequence (roll pitch yaw)
Roll_Yaw_Pitch	XZY sequence (roll yaw pitch)
Pitch_Yaw_Roll	YZX sequence (pitch yaw roll)
Pitch_Roll_Yaw	YXZ sequence (pitch roll yaw)
Yaw_Roll_Pitch	ZXY sequence (yaw roll pitch)
Yaw_Pitch_Roll	ZYX sequence (yaw pitch roll)
RollPitchYaw	XYX sequence (roll pitch yaw)
RollYawPitch	XZY sequence (roll yaw pitch)
PitchYawRoll	YZX sequence (pitch yaw roll)
PitchRollYaw	YXZ sequence (pitch roll yaw)
YawRollPitch	ZXY sequence (yaw roll pitch)
YawPitchRoll	ZYX sequence (yaw pitch roll)

Definition at line 102 of file orientation.hh.

7.2.3 Constructor & Destructor Documentation

7.2.3.1 Orientation() [1/5]

```
jeod::Orientation::Orientation ( ) [default]
```

7.2.3.2 ~Orientation()

```
virtual jeod::Orientation::~~Orientation ( ) [virtual], [default]
```

7.2.3.3 Orientation() [2/5]

```
jeod::Orientation::Orientation (
    const double trans_in[3][3] ) [explicit]
```

Construct an [Orientation](#) instance from a transformation matrix.

Parameters

in	<i>trans_in</i>	Transformation matrix
----	-----------------	-----------------------

Definition at line 54 of file orientation.cc.

References [trans](#).

7.2.3.4 Orientation() [3/5]

```
jeod::Orientation::Orientation (
    const Quaternion & quat_in ) [explicit]
```

Construct an [Orientation](#) instance from a Quaternion.

Parameters

in	<i>quat_in</i>	Quaternion
----	----------------	------------

Definition at line 65 of file orientation.cc.

7.2.3.5 Orientation() [4/5]

```
jeod::Orientation::Orientation (
    double eigen_angle_in,
    const double eigen_axis_in[3] ) [explicit]
```

Construct an [Orientation](#) instance from an eigen rotation.

Parameters

in	<i>eigen_angle↔ _in</i>	Rotation angle Units: r
in	<i>eigen_axis_in</i>	Rotation axis, unit vector

Definition at line 77 of file orientation.cc.

References [eigen_axis](#).

7.2.3.6 Orientation() [5/5]

```
jeod::Orientation::Orientation (
    EulerSequence sequence_in,
    const double angles_in[3] ) [explicit]
```

Construct an [Orientation](#) instance from an Euler rotation.

Parameters

in	<i>sequence↔ _in</i>	Euler sequence
in	<i>angles_in</i>	Euler angles Units: r

Definition at line 90 of file orientation.cc.

References [euler_angles](#).

7.2.4 Member Function Documentation

7.2.4.1 clear_euler_sequence()

```
void jeod::Orientation::clear_euler_sequence ( )
```

Reset the `euler_sequence` data member.

Issues arise if the data source is the Euler rotation sequence. The resolution is to preserve the existing input elsewhere.

Definition at line 696 of file orientation.cc.

References [compute_matrix_from_euler_angles\(\)](#), [compute_quaternion_from_euler_angles\(\)](#), [data_source](#), [euler_sequence](#), [have_euler_angles_](#), [have_quaternion_](#), [have_transformation_](#), [InputEulerRotation](#), [InputMatrix](#), and [NoSequence](#).

Referenced by [set_euler_sequence\(\)](#).

7.2.4.2 compute_all_products()

```
void jeod::Orientation::compute_all_products ( ) [virtual]
```

Compute all represented charts on SO3 from the specified source.

Definition at line 414 of file orientation.cc.

References compute_eigen_rotation(), compute_euler_angles(), compute_quaternion(), and compute_transform().

7.2.4.3 compute_eigen_rotation()

```
void jeod::Orientation::compute_eigen_rotation ( ) [virtual]
```

Compute the eigen rotation from the source.

Definition at line 292 of file orientation.cc.

References compute_eigen_rotation_from_matrix(), compute_matrix_from_euler_angles(), data_source, eigen_angle, eigen_axis, have_eigen_rotation_, have_transformation_, InputEigenRotation, InputEulerRotation, InputMatrix, InputNone, InputQuaternion, mark_input_as_available(), and quat.

Referenced by compute_all_products(), and get_eigen_rotation().

7.2.4.4 compute_eigen_rotation_from_matrix() [1/2]

```
void jeod::Orientation::compute_eigen_rotation_from_matrix (
    const double trans[3][3],
    double * eigen_angle,
    double eigen_axis[3] ) [static]
```

Compute the eigen rotation from the transformation matrix.

There are several alternate expressions for computing the eigen rotation from a matrix, all of which are equivalent in infinite precision arithmetic. The use of finite precision arithmetic means that care must be taken in choosing the algorithm to be used. The starting point is the generic expression

$$T_{ij} = \cos \phi \delta_{ij} + (1 - \cos \phi) \hat{u}_i \hat{u}_j + \epsilon_{ijk} \sin \phi \hat{u}_k$$

From this, the trace of the matrix and the difference between and sum of pairs of off-diagonal elements are

$$\begin{aligned} \text{tr}(T) &= 2 \cos \phi + 1 \\ T_{ij} - T_{ji} &= 2 \epsilon_{ijk} \sin \phi \hat{u}_k \\ T_{ij} + T_{ji} &= 2(1 - \cos \phi) \hat{u}_i \hat{u}_j \end{aligned}$$

Method 1

One approach to determining the eigen rotation involves the construction of a vector of differences between pairs of off-diagonal elements of the transformation matrix,

$$d_k = T_{ij} - T_{ji} = 2 \sin \phi \hat{u}_k$$

where (i,j,k) is an even permutation of (0,1,2). With this,

$$\begin{aligned}\phi &= \arcsin\left(\frac{\|\mathbf{d}\|}{2}\right) \\ \hat{\mathbf{u}} &= \frac{\mathbf{d}}{\|\mathbf{d}\|}\end{aligned}$$

Note that the above of the inverse sine will restrict the rotation angle to be between 0 and 90 degrees. Special processing is needed when the rotation angle is between 90 and 180 degrees. Note also that the symmetric difference vector will be identically zero if the rotation angle is 0 or 180 degrees and will be very small for rotation angles close to 0 or 180 degrees. The precision loss for rotation angles near 0 and 180 degrees means the individual components of the eigen axis will not be as precise with this approach compared to alternatives.

Method 2

The diagonal elements of the matrix yields another method for determining the single axis rotation angle and the rotation axis:

$$\begin{aligned}\phi &= \arccos\left(\frac{\text{tr}(T) - 1}{2}\right) \\ |\hat{u}_i| &= \sqrt{\frac{T_{ii} - \cos \phi}{1 - \cos \phi}}\end{aligned}$$

Note that this approach determines the magnitudes but not the signs of the components of the eigen axis vector. Because this method is based on the inverse cosine, the calculated phi angle will be less precise than that obtained by method 1 for angles near 0 or 180 degrees. The unit vector however will be more accurate than that obtained from method 1 for small rotation angles.

Method 3

Yet another alternative for computing components of the eigen axis is to use the sum of pairs of off-diagonal elements of the transformation matrix,

$$\begin{aligned}T_{ij} + T_{ji} &= 2(1 - \cos \phi) \hat{u}_i \hat{u}_j \\ T_{ik} + T_{ki} &= 2(1 - \cos \phi) \hat{u}_i \hat{u}_k\end{aligned}$$

This enables the calculation of two components of the unit vector. One component needs to be computed by one of the two previous methods.

Assumptions and Limitations

- The matrix is a proper transformation matrix.

Parameters

in	<i>trans</i>	Transformation matrix
out	<i>eigen_angle</i>	Resultant rotation angle Units: r
out	<i>eigen_axis</i>	Resultant rotation axis

Definition at line 194 of file eigen_rotation.cc.

References eigen_angle, eigen_axis, and trans.

7.2.4.5 compute_eigen_rotation_from_matrix() [2/2]

```
void jeod::Orientation::compute_eigen_rotation_from_matrix ( ) [inline], [protected]
```

Compute a eigen rotation that corresponds to the provided transformation matrix.

Definition at line 316 of file orientation.hh.

Referenced by compute_eigen_rotation().

7.2.4.6 compute_euler_angles()

```
void jeod::Orientation::compute_euler_angles ( ) [virtual]
```

Compute the eigen rotation from the source.

Definition at line 344 of file orientation.cc.

References compute_euler_angles_from_matrix(), compute_matrix_from_eigen_rotation(), data_source, euler↵_sequence, EulerXYZ, EulerZYX, have_euler_angles_, have_transformation_, InputEigenRotation, InputEuler↵Rotation, InputMatrix, InputNone, InputQuaternion, jeod::OrientationMessages::invalid_enum, mark_input_as_↵available(), quat, and trans.

Referenced by compute_all_products(), and get_euler_angles().

7.2.4.7 compute_euler_angles_from_matrix() [1/2]

```
void jeod::Orientation::compute_euler_angles_from_matrix (
    const double trans[3][3],
    EulerSequence euler_sequence,
    double euler_angles[3] ) [static]
```

Extract an Euler sequence from the transformation matrix.

A transformation matrix constructed from an XYZ Euler sequence is of the form

$$\begin{bmatrix} \cos \psi \cos \theta & \dots & \dots \\ -\sin \psi \cos \theta & \dots & \dots \\ \sin \theta & -\cos \theta \sin \phi & \cos \theta \cos \phi \end{bmatrix}$$

Note that the [2][0] element of the matrix depends on theta only. The other two elements of the leftmost column are simple terms that depend on theta and psi only, and the other two elements of the bottommost row are simple terms that depend on theta and phi only. Those five elements are the key to extracting an XYZ Euler sequence from a transformation matrix. The same principle applies to all twelve of the Euler sequences: Five key elements contain all of the information needed to extract the desired sequence. The location and form of those key elements of course depends on the sequence.

A problem arises in the above when cos(theta) is zero, or nearly so. This situation is called 'gimbal lock'. Those four elements used to determine phi and psi are zero or nearly so. Fortunately That ugly stuff isn't so ugly in the case of gimbal lock. Once again looking at the matrix generated from an XYZ Euler sequence, when theta=pi/2 the matrix becomes

$$\begin{bmatrix} 0 & \sin(\phi + \psi) & -\cos(\phi + \psi) \\ 0 & \cos(\phi + \psi) & \sin(\phi + \psi) \\ 1 & 0 & 0 \end{bmatrix}$$

In this case there no way to determine both phi and psi; all that can be determined is their sum. One way to overcome this problem is to arbitrarily set one of those angles to an arbitrary value such as zero. That is the approach used in this method. This arbitrary setting enables an XYZ Euler sequence to be extracted from the matrix even in the case of gimbal lock. The same principle once again applies to all twelve sequences.

In summary, for a transformation matrix corresponding to an XYZ sequence,

- The [2][0] element of the matrix specifies theta.
- The [1][0] and [0][0] elements of the matrix specify psi.
- The [2][1] and [2][2] elements of the matrix specify phi. These psi and phi values are valid only when gimbal lock is not present.
- The [1][2] and [1][1] elements of the matrix specify phi in the case of gimbal lock.

Extending this analysis to the remaining eleven sequences provides the essential information needed to extract the desired Euler angles from a transformation matrix. This information is captured in the [EulerInfo](#) array `Euler_info` defined at the head of this file. With a reference `info` to the appropriate element of this array,

- The `[info.indices[2]][info.indices[0]]` element of the matrix specifies the angle theta.
- The `[info.indices[1]][info.indices[0]]` and `[info.alternate_x][info.indices[0]]` elements of the matrix specify the angle psi when gimbal lock is not present.
- The `[info.indices[2]][info.indices[1]]` and `[info.indices[2]][info.alternate_z]` elements of the matrix specify the angle phi when gimbal lock is not present.
- The `[info.indices[1]][info.alternate_z]` and `[info.indices[1]][info.indices[1]]` elements of the matrix specify angle phi when gimbal lock is present.

Assumptions and Limitations

- To within numerical accuracy, the transformation matrix in the [Orientation](#) object *is* a proper transformation matrix:
 - The magnitude of each row and column vector is nearly one.
 - The inner product of any two different rows / two different columns of the matrix nearly zero.
 - The determinant of the matrix is nearly one.
 - An element whose value is outside the range $[-1, 1]$ is only slightly outside that range and the deviation is numerical.

Parameters

in	<i>trans</i>	Transformation matrix
in	<i>euler_sequence</i>	Euler sequence
out	<i>euler_angles</i>	Resultant Euler angles Units: r

Definition at line 297 of file `euler_angles.cc`.

References `jeod::EulerInfo::alternate_x`, `jeod::EulerInfo::alternate_z`, `euler_angles`, `jeod::Euler_info`, `euler_↵sequence`, `EulerXYZ`, `EulerZYZ`, `gimbal_lock_threshold`, `jeod::EulerInfo::indices`, `jeod::OrientationMessages↵::invalid_enum`, `jeod::EulerInfo::is_aerodynamics_sequence`, `jeod::EulerInfo::is_even_permutation`, and `trans`.

7.2.4.8 compute_euler_angles_from_matrix() [2/2]

```
void jeod::Orientation::compute_euler_angles_from_matrix ( ) [inline], [protected]
```

Compute an Euler rotation sequence that corresponds to the provided transformation matrix.

Definition at line 298 of file `orientation.hh`.

Referenced by `compute_euler_angles()`.

7.2.4.9 compute_matrix_from_eigen_rotation() [1/2]

```
void jeod::Orientation::compute_matrix_from_eigen_rotation (
    double eigen_angle,
    const double eigen_axis[3],
    double trans[3][3] ) [static]
```

Compute the transformation matrix from the eigen rotation.

Given a rotation by an angle ϕ about an axis \hat{u} , the $[[i][j]]$ element of the transformation matrix is given by

$$T_{ij} = \cos \phi \delta_{ij} + (1 - \cos \phi) \hat{u}_i \hat{u}_j + \epsilon_{ijk} \sin \phi \hat{u}_k$$

where

- δ_{ij} is the Kronecker delta,
- k is $(i + j) \bmod 3$, and
- ϵ_{ijk} is the Levi-Civita symbol taken with respect to (0,1,2).

Assumptions and Limitations

- The eigen axis is a unit vector.

Parameters

in	<i>eigen_angle</i>	Rotation angle Units: r
in	<i>eigen_axis</i>	Rotation axis, unit vector
out	<i>trans</i>	Resultant transformation matrix

Definition at line 81 of file eigen_rotation.cc.

References eigen_angle, eigen_axis, and trans.

7.2.4.10 compute_matrix_from_eigen_rotation() [2/2]

```
void jeod::Orientation::compute_matrix_from_eigen_rotation ( ) [inline], [protected]
```

Compute the transformation matrix that corresponds to the provided eigen rotation.

Definition at line 307 of file orientation.hh.

Referenced by compute_euler_angles(), and compute_transform().

7.2.4.11 compute_matrix_from_euler_angles() [1/2]

```
void jeod::Orientation::compute_matrix_from_euler_angles (
    EulerSequence euler_sequence,
    const double euler_angles[3],
    double trans[3][3] ) [static]
```

Compute the transformation matrix from the Euler sequence.

The matrix is formed by generating a sequence of three simple transformation matrices corresponding to the three rotations. The composite transformation matrix is the reverse-order product of these three simple matrices.

Parameters

in	<i>euler_sequence</i>	Euler sequence
in	<i>euler_angles</i>	Euler angles Units: r
out	<i>trans</i>	Resultant transformation matrix

Definition at line 164 of file euler_angles.cc.

References `euler_angles`, `jeod::Euler_info`, `euler_sequence`, `EulerXYZ`, `EulerZYX`, `jeod::EulerInfo::indices`, `jeod::OrientationMessages::invalid_enum`, and `trans`.

7.2.4.12 compute_matrix_from_euler_angles() [2/2]

```
void jeod::Orientation::compute_matrix_from_euler_angles ( ) [inline], [protected]
```

Compute the transformation matrix that corresponds to the provided Euler rotation sequence.

Definition at line 289 of file orientation.hh.

Referenced by `clear_euler_sequence()`, `compute_eigen_rotation()`, and `compute_transform()`.

7.2.4.13 compute_quaternion()

```
void jeod::Orientation::compute_quaternion ( ) [virtual]
```

Compute the left transformation quaternion from the source.

Definition at line 245 of file orientation.cc.

References `compute_quaternion_from_euler_angles()`, `data_source`, `eigen_angle`, `eigen_axis`, `have_quaternion`, `InputEigenRotation`, `InputEulerRotation`, `InputMatrix`, `InputNone`, `InputQuaternion`, `mark_input_as_available()`, `quat`, and `trans`.

Referenced by `compute_all_products()`, `compute_transformation_and_quaternion()`, and `get_quaternion()`.

7.2.4.14 compute_quaternion_from_euler_angles() [1/2]

```
void jeod::Orientation::compute_quaternion_from_euler_angles (
    EulerSequence euler_sequence,
    const double euler_angles[3],
    Quaternion & quat ) [static]
```

Compute the left transformation quaternion from the Euler sequence.

The quaternion is formed by generating a sequence of three simple quaternions corresponding to the three rotations. The composite quaternion is the reverse-order product of these three simple quaternions.

Parameters

in	<i>euler_sequence</i>	Euler sequence
in	<i>euler_angles</i>	Euler angles Units: r
out	<i>quat</i>	Resultant quaternion

Definition at line 121 of file euler_angles.cc.

References `euler_angles`, `jeod::Euler_info`, `euler_sequence`, `EulerXYZ`, `EulerZYX`, `jeod::EulerInfo::indices`, `jeod::OrientationMessages::invalid_enum`, and `quat`.

7.2.4.15 compute_quaternion_from_euler_angles() [2/2]

```
void jeod::Orientation::compute_quaternion_from_euler_angles ( ) [inline], [protected]
```

Compute the left transformation quaternion that corresponds to the provided Euler rotation sequence.

Definition at line 280 of file orientation.hh.

Referenced by `clear_euler_sequence()`, and `compute_quaternion()`.

7.2.4.16 compute_transform()

```
void jeod::Orientation::compute_transform ( ) [virtual]
```

Compute the transformation matrix from the source.

Definition at line 198 of file orientation.cc.

References `compute_matrix_from_eigen_rotation()`, `compute_matrix_from_euler_angles()`, `data_source`, `have_transformation_`, `InputEigenRotation`, `InputEulerRotation`, `InputMatrix`, `InputNone`, `InputQuaternion`, `mark_input_as_available()`, `quat`, and `trans`.

Referenced by `compute_all_products()`, `compute_transformation_and_quaternion()`, and `get_transform()`.

7.2.4.17 compute_transformation_and_quaternion()

```
void jeod::Orientation::compute_transformation_and_quaternion ( ) [virtual]
```

Compute the transformation matrix and quaternion.

Definition at line 425 of file orientation.cc.

References `compute_quaternion()`, and `compute_transform()`.

7.2.4.18 get_eigen_rotation()

```
void jeod::Orientation::get_eigen_rotation (
    double * eigen_angle_out,
    double eigen_axis_out[3] )
```

Accessor for the eigen rotation.

Parameters

out	<i>eigen_angle_out</i>	Copy of the single axis rotation angle Units: r
out	<i>eigen_axis_out</i>	Copy of the single axis rotation axis

Definition at line 485 of file orientation.cc.

References `compute_eigen_rotation()`, `eigen_angle`, `eigen_axis`, and `have_eigen_rotation_`.

7.2.4.19 get_euler_angles() [1/2]

```
void jeod::Orientation::get_euler_angles (
    EulerSequence * sequence,
    double angles[3] )
```

Accessor for the Euler angles.

Parameters

out	<i>sequence</i>	Copy of the Euler sequence
out	<i>angles</i>	Copy of the Euler angles Units: r

Definition at line 505 of file orientation.cc.

References `compute_euler_angles()`, `euler_angles`, `euler_sequence`, and `have_euler_angles_`.

7.2.4.20 `get_euler_angles()` [2/2]

```
void jeod::Orientation::get_euler_angles (
    double angles[3] )
```

Accessor for the Euler angles.

Parameters

out	<i>angles</i>	Copy of the Euler angles Units: r
-----	---------------	--------------------------------------

Definition at line 524 of file orientation.cc.

References `compute_euler_angles()`, `euler_angles`, and `have_euler_angles_`.

7.2.4.21 `get_euler_sequence()`

```
Orientation::EulerSequence jeod::Orientation::get_euler_sequence ( )
```

Accessor for the Euler sequence data member.

Returns

Euler sequence data member

Definition at line 542 of file orientation.cc.

References `euler_sequence`.

7.2.4.22 `get_quaternion()`

```
void jeod::Orientation::get_quaternion (
    Quaternion & quat_out )
```

Accessor for the left transformation quaternion.

Parameters

out	<i>quat_out</i>	Copy of the quaternion
-----	-----------------	------------------------

Definition at line 466 of file orientation.cc.

References `compute_quaternion()`, `have_quaternion_`, and `quat`.

7.2.4.23 get_transform()

```
void jeod::Orientation::get_transform (
    double trans_out[3][3] )
```

Accessor for the transformation matrix.

Parameters

out	trans_out	Copy of the transformation matrix
-----	-----------	-----------------------------------

Definition at line 448 of file orientation.cc.

References compute_transform(), have_transformation_, and trans.

7.2.4.24 mark_input_as_available()

```
void jeod::Orientation::mark_input_as_available ( ) [protected]
```

Mark the item specified by the data_source as available.

Note that this method doesn't compute any products.

Assumptions and Limitations

- The data_source member datum is valid.

Definition at line 127 of file orientation.cc.

References data_source, have_eigen_rotation_, have_euler_angles_, have_quaternion_, have_transformation_↵, InputEigenRotation, InputEulerRotation, InputMatrix, InputNone, InputQuaternion, and jeod::Orientation↵ Messages::invalid_enum.

Referenced by compute_eigen_rotation(), compute_euler_angles(), compute_quaternion(), and compute_↵transform().

7.2.4.25 reset()

```
void jeod::Orientation::reset ( ) [virtual]
```

Forget that we have any data.

Note that this method does not reset the euler_sequence member; that is intentional.

Definition at line 114 of file orientation.cc.

References data_source, have_eigen_rotation_, have_euler_angles_, have_quaternion_, have_transformation_↵, and InputNone.

Referenced by set_eigen_rotation(), set_euler_angles(), set_quaternion(), and set_transform().

7.2.4.26 set_eigen_rotation()

```
void jeod::Orientation::set_eigen_rotation (
    double eigen_angle_in,
    const double eigen_axis_in[3] )
```

Reset the instance with a new eigen rotation.

Parameters

in	<i>eigen_angle↔ _in</i>	New single axis rotation angle
in	<i>eigen_axis_in</i>	New single axis rotation axis

Definition at line 589 of file orientation.cc.

References `data_source`, `eigen_angle`, `eigen_axis`, `have_eigen_rotation_`, `InputEigenRotation`, and `reset()`.

7.2.4.27 set_euler_angles() [1/2]

```
void jeod::Orientation::set_euler_angles (
    EulerSequence sequence,
    const double angles[3] )
```

Reset the instance with a new Euler rotation.

Parameters

in	<i>sequence</i>	New Euler sequence
in	<i>angles</i>	New Euler angles Units: r

Definition at line 604 of file orientation.cc.

References `data_source`, `euler_angles`, `euler_sequence`, `EulerXYZ`, `EulerZYZ`, `have_euler_angles_`, `InputEuler↔
Rotation`, `jeod::OrientationMessages::invalid_enum`, and `reset()`.

7.2.4.28 set_euler_angles() [2/2]

```
void jeod::Orientation::set_euler_angles (
    const double angles[3] )
```

Reset the instance with a new Euler rotation.

Assumptions and Limitations

- The `euler_sequence` data member must have previously been set to a valid value.

Parameters

in	<i>angles</i>	New Euler angles Units: r
----	---------------	------------------------------

Definition at line 636 of file orientation.cc.

References `data_source`, `euler_angles`, `euler_sequence`, `EulerXYZ`, `EulerZYZ`, `have_euler_angles_`, `InputEulerRotation`, `jeod::OrientationMessages::invalid_enum`, and `reset()`.

7.2.4.29 `set_euler_sequence()`

```
void jeod::Orientation::set_euler_sequence (
    EulerSequence sequence )
```

Set the `euler_sequence` data member.

Parameters

in	<i>sequence</i>	New Euler sequence
----	-----------------	--------------------

Definition at line 665 of file `orientation.cc`.

References `clear_euler_sequence()`, `euler_sequence`, `EulerXYZ`, `EulerZYZ`, `have_euler_angles_`, and `jeod::OrientationMessages::invalid_enum`.

7.2.4.30 `set_quaternion()`

```
void jeod::Orientation::set_quaternion (
    const Quaternion & quat_in )
```

Reset the instance with a new quaternion.

Parameters

in	<i>quat_in</i>	New quaternion
----	----------------	----------------

Definition at line 575 of file `orientation.cc`.

References `data_source`, `have_quaternion_`, `InputQuaternion`, `quat`, and `reset()`.

7.2.4.31 `set_transform()`

```
void jeod::Orientation::set_transform (
    const double trans_in[3][3] )
```

Reset the instance with a new matrix.

Parameters

in	<i>trans</i> <i>_in</i>	New transformation matrix
----	----------------------------	---------------------------

Definition at line 562 of file orientation.cc.

References `data_source`, `have_transformation_`, `InputMatrix`, `reset()`, and `trans`.

7.2.5 Friends And Related Function Documentation**7.2.5.1 `init_attrjeod__Orientation`**

```
void init_attrjeod__Orientation ( ) [friend]
```

7.2.5.2 `InputProcessor`

```
friend class InputProcessor [friend]
```

Definition at line 85 of file orientation.hh.

7.2.6 Field Documentation**7.2.6.1 `data_source`**

```
DataSource jeod::Orientation::data_source {InputMatrix}
```

Orientation data source – specifies whether the user has provided as input an Euler rotation, a transformation matrix, or a left transformation quaternion.

`trick_units(-)`

Definition at line 221 of file orientation.hh.

Referenced by `clear_euler_sequence()`, `compute_eigen_rotation()`, `compute_euler_angles()`, `compute_↔quaternion()`, `compute_transform()`, `mark_input_as_available()`, `reset()`, `set_eigen_rotation()`, `set_euler_angles()`, `set_quaternion()`, and `set_transform()`.

7.2.6.2 eigen_angle

```
double jeod::Orientation::eigen_angle {}
```

Single axis rotation angle.

trick_units(rad)

Definition at line 247 of file orientation.hh.

Referenced by compute_eigen_rotation(), compute_eigen_rotation_from_matrix(), compute_matrix_from_eigen↵_rotation(), compute_quaternion(), get_eigen_rotation(), and set_eigen_rotation().

7.2.6.3 eigen_axis

```
double jeod::Orientation::eigen_axis[3] {}
```

Single axis rotation axis unit vector.

trick_units(-)

Definition at line 252 of file orientation.hh.

Referenced by compute_eigen_rotation(), compute_eigen_rotation_from_matrix(), compute_matrix_from_eigen↵_rotation(), compute_quaternion(), get_eigen_rotation(), Orientation(), and set_eigen_rotation().

7.2.6.4 euler_angles

```
double jeod::Orientation::euler_angles[3] {}
```

Euler angles corresponding to rotation sequence euler_sequence.

The elements are stored in the order specified by that sequence.trick_units(rad)

Definition at line 232 of file orientation.hh.

Referenced by compute_euler_angles_from_matrix(), compute_matrix_from_euler_angles(), compute_↵quaternion_from_euler_angles(), get_euler_angles(), Orientation(), and set_euler_angles().

7.2.6.5 euler_sequence

```
EulerSequence jeod::Orientation::euler_sequence {NoSequence}
```

The Euler rotation sequence corresponding to euler_angles.

trick_units(-)

Definition at line 226 of file orientation.hh.

Referenced by clear_euler_sequence(), compute_euler_angles(), compute_euler_angles_from_matrix(), compute_matrix_from_euler_angles(), compute_quaternion_from_euler_angles(), get_euler_angles(), get_euler↵_sequence(), set_euler_angles(), and set_euler_sequence().

7.2.6.6 gimbal_lock_threshold

```
double jeod::Orientation::gimbal_lock_threshold = 1e-13 [static], [protected]
```

Threshold for detecting gimbal lock in `compute_euler_angles_from_matrix`.

The threshold for determining whether a gimbal lock condition exists.

`trick_units(-)`

Gimbal lock occurs when $\sin(\theta)$ (aerodynamics Euler sequences) or $\cos(\theta)$ (astronomical sequences) is very close to -1 or +1. This static variable quantifies the meaning of 'very close'.

Definition at line 144 of file `orientation.hh`.

Referenced by `compute_euler_angles_from_matrix()`.

7.2.6.7 have_eigen_rotation_

```
bool jeod::Orientation::have_eigen_rotation_ {} [protected]
```

True if eigen rotation has been set/computed.

`trick_units(-)`

Definition at line 268 of file `orientation.hh`.

Referenced by `compute_eigen_rotation()`, `get_eigen_rotation()`, `mark_input_as_available()`, `reset()`, and `set_eigen_rotation()`.

7.2.6.8 have_euler_angles_

```
bool jeod::Orientation::have_euler_angles_ {} [protected]
```

True if an Euler rotation has been set/computed.

`trick_units(-)`

Definition at line 273 of file `orientation.hh`.

Referenced by `clear_euler_sequence()`, `compute_euler_angles()`, `get_euler_angles()`, `mark_input_as_available()`, `reset()`, `set_euler_angles()`, and `set_euler_sequence()`.

7.2.6.9 have_quaternion_

```
bool jeod::Orientation::have_quaternion_ {} [protected]
```

True if quaternion has been set/computed.

trick_units(-)

Definition at line 263 of file orientation.hh.

Referenced by clear_euler_sequence(), compute_quaternion(), get_quaternion(), mark_input_as_available(), reset(), and set_quaternion().

7.2.6.10 have_transformation_

```
bool jeod::Orientation::have_transformation_ {} [protected]
```

True if transformation matrix has been set/computed.

trick_units(-)

Definition at line 258 of file orientation.hh.

Referenced by clear_euler_sequence(), compute_eigen_rotation(), compute_euler_angles(), compute_transform(), get_transform(), mark_input_as_available(), reset(), and set_transform().

7.2.6.11 quat

```
Quaternion jeod::Orientation::quat
```

Left transformation unit quaternion.

trick_units(-)

Definition at line 242 of file orientation.hh.

Referenced by compute_eigen_rotation(), compute_euler_angles(), compute_quaternion(), compute_quaternion←_from_euler_angles(), compute_transform(), get_quaternion(), and set_quaternion().

7.2.6.12 trans

```
double jeod::Orientation::trans[3][3] { {1.0, 0.0, 0.0}, {0.0, 1.0, 0.0}, {0.0, 0.0, 1.0} }
```

Transformation matrix.

trick_units(-)

Definition at line 237 of file orientation.hh.

Referenced by `compute_eigen_rotation_from_matrix()`, `compute_euler_angles()`, `compute_euler_angles_from_matrix()`, `compute_matrix_from_eigen_rotation()`, `compute_matrix_from_euler_angles()`, `compute_quaternion()`, `compute_transform()`, `get_transform()`, `Orientation()`, and `set_transform()`.

The documentation for this class was generated from the following files:

- [orientation.hh](#)
- [eigen_rotation.cc](#)
- [euler_angles.cc](#)
- [orientation.cc](#)

7.3 jeod::OrientationMessages Class Reference

Declares messages associated with the orientation model.

```
#include <orientation_messages.hh>
```

Public Member Functions

- [OrientationMessages](#) ()=delete
- [OrientationMessages](#) (const [OrientationMessages](#) &)=delete
- [OrientationMessages](#) & operator= (const [OrientationMessages](#) &)=delete

Static Public Attributes

- static const char * [invalid_enum](#) = "utils/orientation/" "invalid_enum"
Issued when a enum value is not one of the enumerated values.
- static const char * [invalid_data](#) = "utils/orientation/" "invalid_data"
Issued when an orientation specification is invalid.
- static const char * [invalid_request](#) = "utils/orientation/" "invalid_request"
Issued when an requested is invalid.

Friends

- class [InputProcessor](#)
- void [init_attrjeod__OrientationMessages](#) ()

7.3.1 Detailed Description

Declares messages associated with the orientation model.

Definition at line 82 of file orientation_messages.hh.

7.3.2 Constructor & Destructor Documentation

7.3.2.1 OrientationMessages() [1/2]

```
jeod::OrientationMessages::OrientationMessages ( ) [delete]
```

7.3.2.2 OrientationMessages() [2/2]

```
jeod::OrientationMessages::OrientationMessages (
    const OrientationMessages & ) [delete]
```

7.3.3 Member Function Documentation

7.3.3.1 operator=()

```
OrientationMessages& jeod::OrientationMessages::operator= (
    const OrientationMessages & ) [delete]
```

7.3.4 Friends And Related Function Documentation

7.3.4.1 init_attrjeod__OrientationMessages

```
void init_attrjeod__OrientationMessages ( ) [friend]
```

7.3.4.2 InputProcessor

```
friend class InputProcessor [friend]
```

Definition at line 84 of file orientation_messages.hh.

7.3.5 Field Documentation

7.3.5.1 invalid_data

```
char const * jeod::OrientationMessages::invalid_data = "utils/orientation/" "invalid_data"  
[static]
```

Issued when an orientation specification is invalid.

trick_units(—)

Definition at line 94 of file orientation_messages.hh.

7.3.5.2 invalid_enum

```
char const * jeod::OrientationMessages::invalid_enum = "utils/orientation/" "invalid_enum"  
[static]
```

Issued when a enum value is not one of the enumerated values.

trick_units(—)

Definition at line 89 of file orientation_messages.hh.

Referenced by jeod::Orientation::compute_euler_angles(), jeod::Orientation::compute_euler_angles_from_↵
matrix(), jeod::Orientation::compute_matrix_from_euler_angles(), jeod::Orientation::compute_quaternion_from_↵
_euler_angles(), jeod::Orientation::mark_input_as_available(), jeod::Orientation::set_euler_angles(), and jeod::↵
Orientation::set_euler_sequence().

7.3.5.3 invalid_request

```
char const * jeod::OrientationMessages::invalid_request = "utils/orientation/" "invalid_↵  
request" [static]
```

Issued when an requested is invalid.

trick_units(—)

Definition at line 99 of file orientation_messages.hh.

The documentation for this class was generated from the following files:

- [orientation_messages.hh](#)
- [orientation_messages.cc](#)

Chapter 8

File Documentation

8.1 `eigen_rotation.cc` File Reference

Define Orientation methods related to computing single axis rotations.

```
#include <cmath>
#include "utils/math/include/matrix3x3.hh"
#include "utils/math/include/vector3.hh"
#include "../include/orientation.hh"
```

Namespaces

- [jeod](#)

Namespace jeod.

8.1.1 Detailed Description

Define Orientation methods related to computing single axis rotations.

8.2 `euler_angles.cc` File Reference

Define Orientation methods related to computing Euler angles.

```
#include <cmath>
#include "utils/math/include/matrix3x3.hh"
#include "utils/message/include/message_handler.hh"
#include "../include/orientation.hh"
#include "../include/orientation_messages.hh"
```

Data Structures

- struct [jeod::EulerInfo](#)

Contains data needed to construct a transformation matrix given a sequence of Euler angles and to extract a sequence of Euler angles from a matrix.

Namespaces

- [jeod](#)

Namespace jeod.

Variables

- static const EulerInfo [jeod::Euler_info](#) [12]

Contains twelve [EulerInfo](#) objects, one per each of the JEOD Euler sequences.

8.2.1 Detailed Description

Define Orientation methods related to computing Euler angles.

8.3 orientation.cc File Reference

Define methods for the NewOrientation class.

```
#include <cmath>
#include "utils/math/include/matrix3x3.hh"
#include "utils/math/include/vector3.hh"
#include "utils/message/include/message_handler.hh"
#include "../include/orientation.hh"
#include "../include/orientation_messages.hh"
```

Namespaces

- [jeod](#)

Namespace jeod.

8.3.1 Detailed Description

Define methods for the NewOrientation class.

8.4 orientation.hh File Reference

Define the Orientation class.

```
#include "utils/quaternion/include/quat.hh"
#include "utils/sim_interface/include/jeod_class.hh"
#include "utils/math/include/macro_def.hh"
#include "utils/math/include/macro_undef.hh"
```

Data Structures

- class [jeod::Orientation](#)

Specifies the orientation of one reference frame with respect to another.

Namespaces

- [jeod](#)

Namespace jeod.

8.4.1 Detailed Description

Define the Orientation class.

8.5 orientation_messages.cc File Reference

Implement the class OrientationMessages.

```
#include "utils/message/include/make_message_code.hh"
#include "../include/orientation_messages.hh"
```

Namespaces

- [jeod](#)

Namespace jeod.

Macros

- `#define MAKE_ORIENTATION_MESSAGE_CODE(id) JEOD_MAKE_MESSAGE_CODE(Orientation↔Messages, "utils/orientation/", id)`

8.5.1 Detailed Description

Implement the class OrientationMessages.

8.5.2 Macro Definition Documentation

8.5.2.1 MAKE_ORIENTATION_MESSAGE_CODE

```
#define MAKE_ORIENTATION_MESSAGE_CODE(  
    id ) JEOD_MAKE_MESSAGE_CODE(OrientationMessages, "utils/orientation/", id)
```

Definition at line 37 of file orientation_messages.cc.

8.6 orientation_messages.hh File Reference

Define the class OrientationMessages, the class that specifies the message IDs used in the orientation model.

```
#include "utils/sim_interface/include/jeod_class.hh"
```

Data Structures

- class [jeod::OrientationMessages](#)
Declares messages associated with the orientation model.

Namespaces

- [jeod](#)
Namespace jeod.

8.6.1 Detailed Description

Define the class OrientationMessages, the class that specifies the message IDs used in the orientation model.

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