Homework 2

Table of Contents

Bailey Waterman, Keshuai Xu

1

1. Phase-shift keying 2. False 3. Sheer distance between satellite and reciever

2a

```
clear variables; close all; clc;

v_e = [10 0 0]'; % units
R_i_e = rotx(deg2rad(13))*roty(deg2rad(15))*rotz(deg2rad(10));

v_i = R_i_e \ v_e % units
```

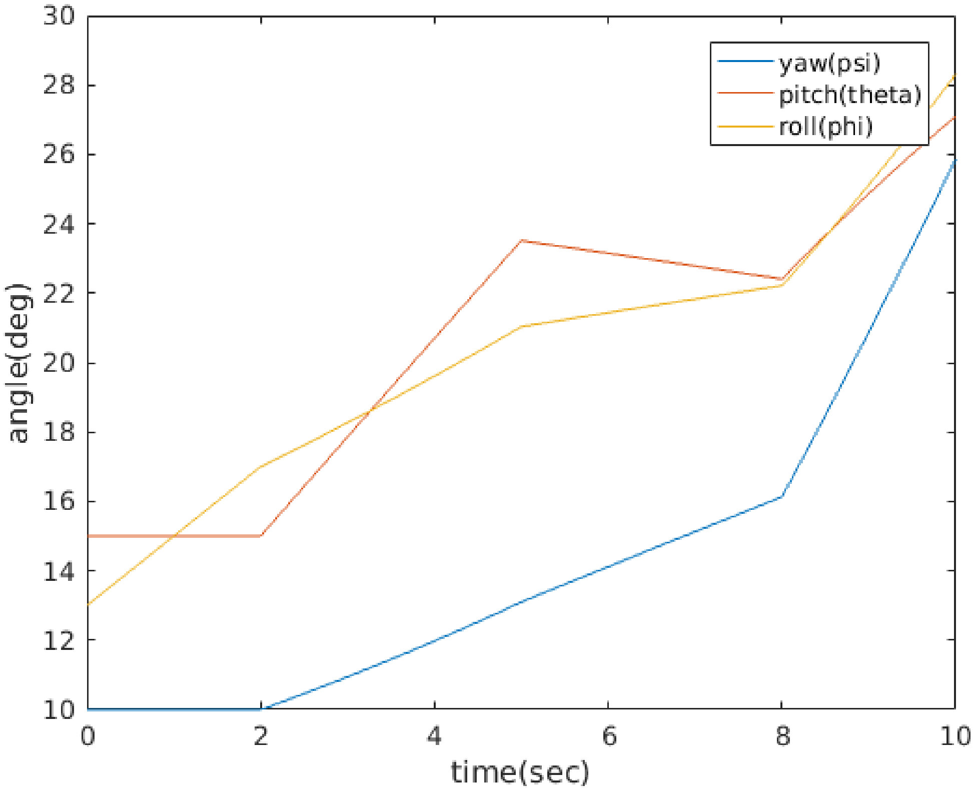
```
v_i =

    9.9998
   -0.0305
    0.0457
```

2b

```
function euler321_angles_dot = rotational_kinematics(t,
 euler321_angles, omega_iee)

psi_yaw = euler321_angles(1);
theta_pitch = euler321_angles(2);
phi_roll = euler321_angles(3);

H_321 = [-sin(theta_pitch) 0 1;
    sin(phi_roll)*cos(theta_pitch) cos(phi_roll) 0;
    cos(phi_roll)*cos(theta_pitch) -sin(phi_roll) 0];

euler321_angles_dot = H_321 \ omega_iee;
end
```

```
clear variables; close all; clc;

%initial conditions
euler321_angles_initial = [10; 15; 13] * pi/180; %radians
time_span = [0 2]; %seconds
omega_iee = [2; 0; 0;] *pi/180; %radians/second

%solve ODE
[t_sim, euler321_angles_sim] = ...
ode45(@(t, y)rotational_kinematics(t, y, omega_iee), time_span,
 euler321_angles_initial);

%initial conditions same as last ones
euler321_angles_initial = euler321_angles_sim(end, :); %rad
time_span = [2 5]; %s
omega_iee = [1; 3; 0;] * pi/180; %rad/s

%solve ODE
[t_sim_2, euler321_angles_sim_2] = ...
ode45(@(t, y)rotational_kinematics(t, y, omega_iee), time_span,
 euler321_angles_initial);

%initial conditions same as last ones
euler321_angles_initial = euler321_angles_sim_2(end, :); %rad
time_span = [5 8]; %s
omega_iee = [0; 0; 1;] * pi/180; %rad/s

%solve ODE
[t_sim_3, euler321_angles_sim_3] = ...
ode45(@(t, y)rotational_kinematics(t, y, omega_iee), time_span,
 euler321_angles_initial);

%initial conditions same as last ones
euler321_angles_initial = euler321_angles_sim_3(end, :); %rad
time_span = [8 10]; %s
omega_iee = [1; 4; 3;] * pi/180; %rad/s

%solve ODE
[t_sim_4, euler321_angles_sim_4] = ...
ode45(@(t, y)rotational_kinematics(t, y, omega_iee), time_span,
 euler321_angles_initial);

euler321_angles_degrees_1 = euler321_angles_sim * 180/pi;
euler321_angles_degrees_2 = euler321_angles_sim_2 * 180/pi;
euler321_angles_degrees_3 = euler321_angles_sim_3 * 180/pi;
euler321_angles_degrees_4 = euler321_angles_sim_4 * 180/pi;

time = [t_sim; t_sim_2; t_sim_3; t_sim_4;];
euler321_angles_degrees = [euler321_angles_degrees_1;
 euler321_angles_degrees_2; euler321_angles_degrees_3;
 euler321_angles_degrees_4;];
```

```
plot(time, euler321_angles_degrees)

xlabel('time(sec)')
ylabel ('angle(deg)')
legend ('yaw(psi)','pitch(theta)','roll(phi)')
```

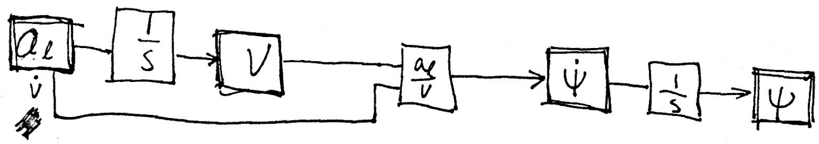


3

from example 7.6

$$\dot{\underline{v}}^i = R_e^i(\dot{\underline{v}}^e + \underline{\tilde{\omega}}_{ie}^e \underline{v}^e) = \begin{bmatrix} \dot{v}\cos\psi - \dot{\psi} v \sin\psi \\ \dot{v}\sin\psi + \dot{\psi} v \cos\psi \\ 0 \end{bmatrix}$$

$$\dot{\psi} = \frac{a_\ell}{v} \qquad v = \int a_\ell \, dt \qquad \psi = \int \dot{\psi} \, dt$$



t	a_ℓ	v	$\dot{\psi}$	ψ
$0 \to 10$	5	5	1	t
$t = 10 \to 25$	0	$5(t-10)$	0	0
$25 \to 35$	5	$5(t-10)$	$\frac{1}{t-10}$	$\cancel{t}$ $\ln(t-10)$
$35 \to 40$	0	125	0	0

$a_\ell, v, \dot{\psi}, \psi$ are piecewise functions of t.

$$y = \begin{bmatrix} p^i \\ \dot{p}^i \end{bmatrix} \qquad \dot{y} = \begin{bmatrix} \dot{p}^i \\ \ddot{p}^i \end{bmatrix} = \begin{bmatrix} y_2 \\ \dot{v}^i(t) \end{bmatrix}$$

```
function [ a_l ] = hw2_a_l( t )
%HW2_A_L Summary of this function goes here
%   Detailed explanation goes here
```

```
if t < 0; a_l = 5; warning('out of bound'); end;
if t < 10; a_l = 5; return; end;
if t < 25; a_l = 0; return; end;
if t < 35; a_l = 5; return; end;
if t < 40; a_l = 0; return; end;
a_l = 0;
warning('out of bound');

end
```

```
function [ a_t ] = hw2_a_t( t )
%UNTITLED7 Summary of this function goes here
%   Detailed explanation goes here
if t < 0; a_t = 0; warning('out of bound'); end;
if t < 10; a_t = 0; return; end;
if t < 25; a_t = 5; return; end;
if t < 35; a_t = 5; return; end;
if t < 40; a_t = 0; return; end;
a_t = 0;
warning('out of bound');

end
```

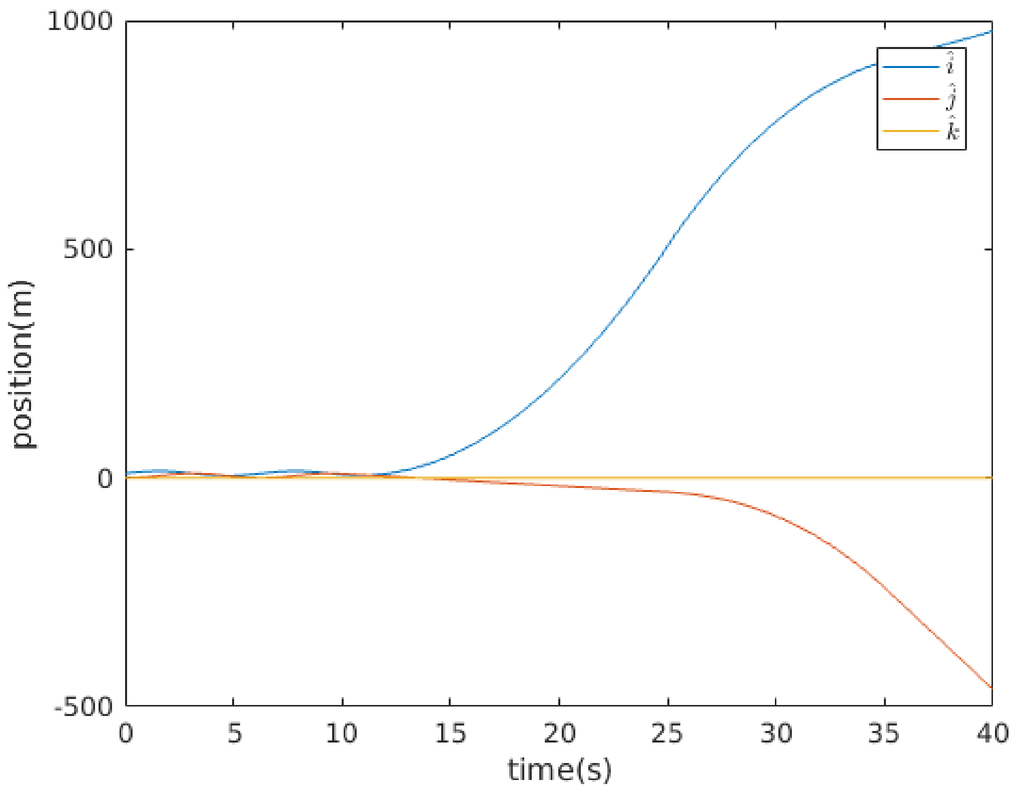
```
function [ psi ] = hw2_psi( t )
%UNTITLED6 Summary of this function goes here
%   Detailed explanation goes here
if t < 0; psi = t; warning('out of bound'); end;
if t < 10; psi = t; return; end;
if t < 25; psi = 0; return; end;
if t < 35; psi = log(t-10); return; end;
if t < 40; psi = 0; return; end;
psi = 0;
warning('out of bound');

end
```

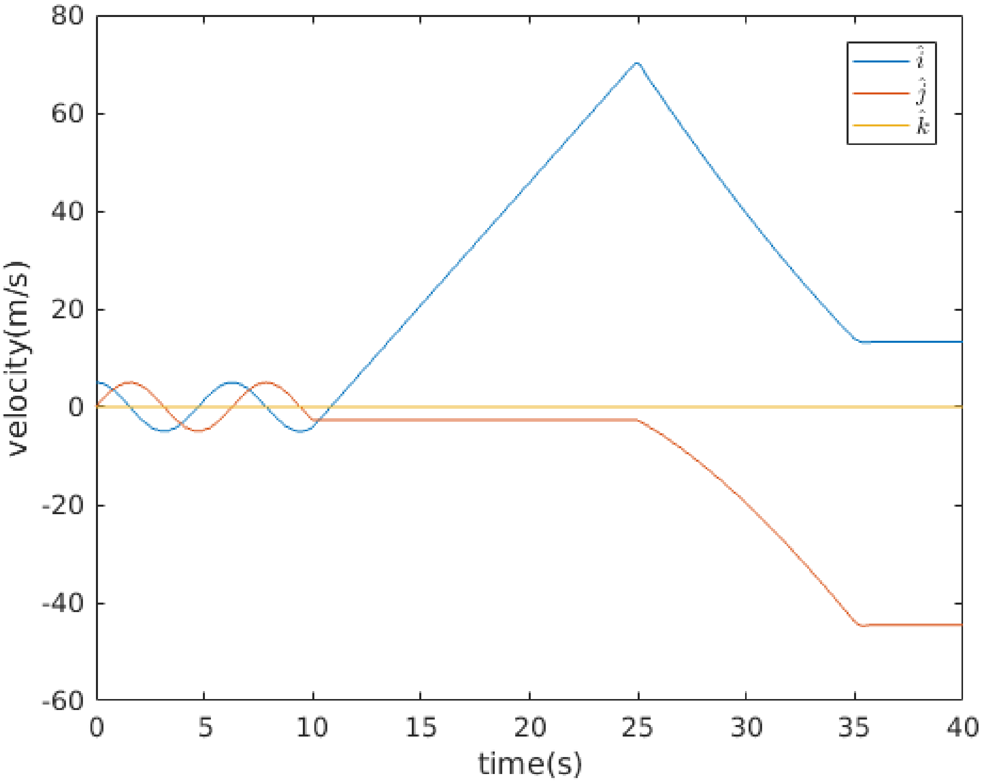
```
function [ psi_dot ] = hw2_psi_dot( t )
%UNTITLED5 Summary of this function goes here
%   Detailed explanation goes here
if t < 0; psi_dot = 1; warning('out of bound'); end;
if t < 10; psi_dot = 1; return; end;
if t < 25; psi_dot = 0; return; end;
if t < 35; psi_dot = 1/(t-10); return; end;
if t < 40; psi_dot = 0; return; end;
psi_dot = 0;
warning('out of bound');
```

```
end



function [ v ] = hw2_v( t )
%UNTITLED4 Summary of this function goes here
%   Detailed explanation goes here

if t < 0; v = 5; warning('out of bound'); end;
if t < 10; v = 5; return; end;
if t < 25; v = 5*(t-10); return; end;
if t < 35; v = 5*(t-10); return; end;
if t < 40; v = 5*(35-10); return; end;
v = 5*(35-10);
warning('out of bound');

end



clear variables; close all; clc;

% from the derivation on the paper, v_dot_i is a piecewise function of
 t.
v_dot_i = @(t) [hw2_a_t(t)*cos(hw2_psi(t)) -
 hw2_psi_dot(t)*hw2_v(t)*sin(hw2_psi(t));
            hw2_a_t(t)*sin(hw2_psi(t)) +
 hw2_psi_dot(t)*hw2_v(t)*cos(hw2_psi(t));
            0];

% in odefun and initial conditon y0,
% y(1:3, :) = p_i (position in m)
% y(4:6, :) = v_i (velocity in m/s)

odefun = @(t,y) [y(4:6, :); v_dot_i(t)];
y0 = [10 0 0 5 0 0]';
warning('off','all')
[t_sim, y_sim] = ode45(odefun, [0 40], y0);
warning('on','all')

figure();
plot(t_sim, y_sim(:, 1:3));
xlabel('time(s)')
ylabel('position(m)')
legend({'$\hat{i}$', '$\hat{j}$', '$\hat{k}$'},'Interpreter','latex')
figure();
plot(t_sim, y_sim(:, 4:6));
xlabel('time(s)')
ylabel('velocity(m/s)')
legend({'$\hat{i}$', '$\hat{j}$', '$\hat{k}$'},'Interpreter','latex')
% at t=40 in I frame,
position = y_sim(end, 1:3)' % m
```

```
velocity = y_sim(end, 4:6)' % m/s
```

```
position =

  977.1305
 -462.6104
         0


velocity =

   13.2583
  -44.5351
         0
```





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