Glossary

a Acceleration vector. $\mathbf{a} = [a_X \quad a_Y \quad a_Z]^T$.

Ψ Attitude vector. $\Psi = [\phi \quad \theta \quad \psi]^T$.

NED Local inertial frame where the X-axis is pointing towards the true North, the Y-axis towards the East and the Z-axis is Down completing the right-hand rule.

PID Controller with Proportional, Integral and Derivative actions.

ψ Yaw euler angle. Also named *Heading*.

r Position vector $\mathbf{r} = [X \quad Y \quad Z]^T$.

ϕ Roll euler angle. Also named *Bank angle* in aviation.

θ Pitch euler angle.

v Velocity vector. $\mathbf{v} = \dot{\mathbf{r}} = [v_X \quad v_Y \quad v_Z]^T$.