

# Glossary

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

$\Psi$  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.

$\psi$  Yaw euler angle. Also named *Heading*.

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

$\phi$  Roll euler angle. Also named *Bank angle* in aviation.

$\theta$  Pitch euler angle.

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