# Quadcopter Naming Conventions

## Reference Frames

|  |  |
| --- | --- |
| Full Name | Simulink Moniker |
| Body | body |
| North-East-Down (NED) | ned |
|  |  |

## Subsystem In/Out Ports

| Item | Example | Convention | Units |
| --- | --- | --- | --- |
| Quaternion | q\_body\_NED | The first part of the name shall be ‘q\_’, followed by the Simulink moniker of the reference frame that is being located, followed by the Simulink moniker of the reference frame that the other frame is being located relative to. The quaternion is represented in scalar-first form. | N/A |
| Angular Velocity | omega\_body | Start with ‘omega\_’, followed by the reference frame in which the angular rate is measured. | rad/s |
| Angular Acceleration | alpha\_body | Start with ‘alpha\_’, followed by the reference frame in which the angular acceleration is measured. | rad/s2 |
| Position | x\_NED | Start with ‘x\_’, followed by the reference frame in which the principal axes of the measurement are defined. | Frame-dependent |
| Velocity | v\_NED | Start with ‘v\_’, followed by the reference frame in which the principal axes of the measurement are defined. | m/s |
| Acceleration | a\_NED | Start with ‘a\_’, followed by the reference frame in which the principal axes of the measurement are defined. | m/s2 |
|  |  |  |  |