EE 570: Location and Navigation

Navigation Mathematics: Rotation Matrices

Kevin Wedeward   Aly El-Osery

Electrical Engineering Department, New Mexico Tech
Socorro, New Mexico, USA

In Collaboration with
Stephen Bruder
Electrical and Computer Engineering Department
Embry-Riddle Aeronautical Univesity
Prescott, Arizona, USA

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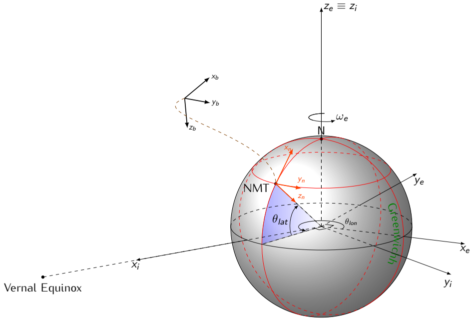
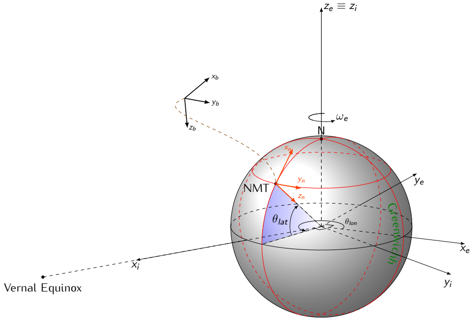
Lecture Topics

1. Review
2. Attitude (Orientation)
3. Rotation Matrices
4. Examples
5. Summary


$z_e \equiv z_i$
x_b
y_b
z_b
ω_e
N
x_n
y_n
z_n
NMT
y_e
θ_{lat}
θ_{lon}
Greenwich
x_e
x_i
y_i
Vernal Equinox

- Coordinate Frames – note subscript will "name" axes (vectors)



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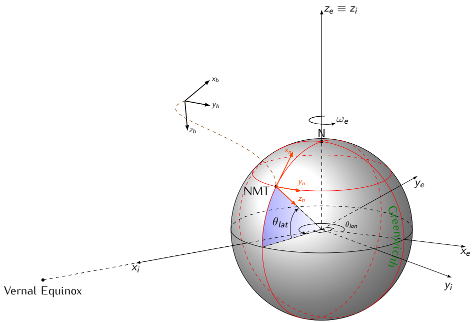

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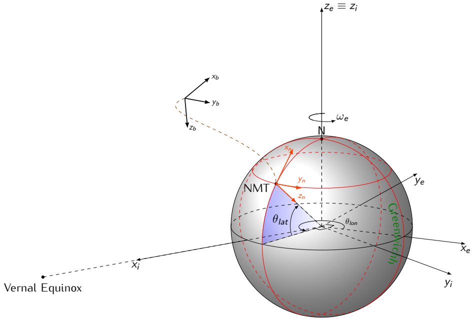
- Earth-Centered Earth-Fixed (ECEF) Frame – e



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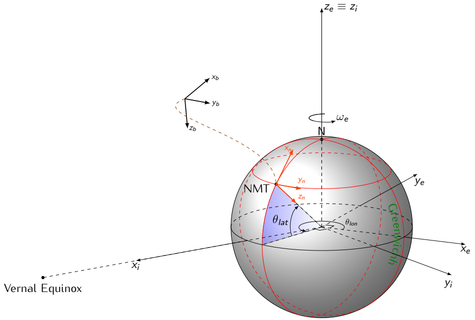
- Navigation (Nav) Frame – n



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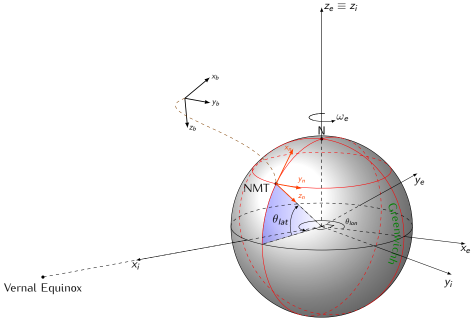
- Navigation (Nav) Frame – *n*
- Body Frame – *b*



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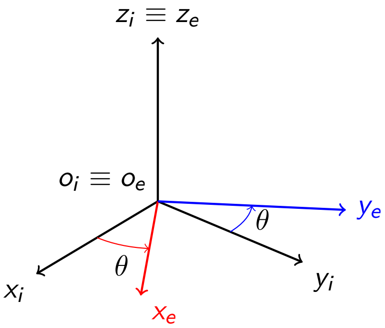

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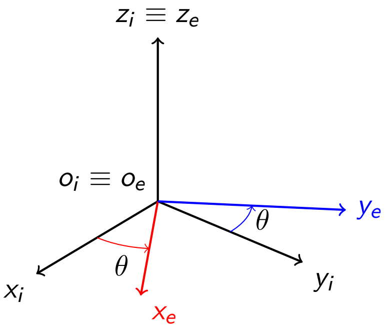

- $e-$frame rotated away from $i-$frame by angle θ about $z_i \equiv z_e$

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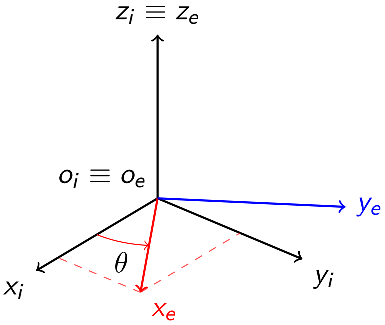
- x_e^i:



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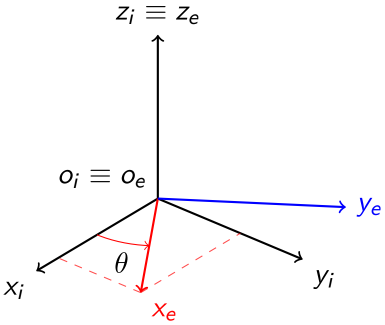
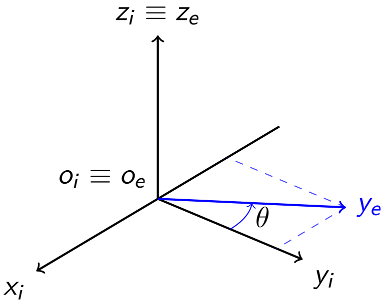


- $x_e^i = \begin{bmatrix} x_e \cdot x_i \\ x_e \cdot y_i \\ x_e \cdot z_i \end{bmatrix} = \begin{bmatrix} \|x_e\| \|x_i\| \cos(\theta) \\ \|x_e\| \|y_i\| \cos(90^\circ - \theta) \\ \|x_e\| \|z_i\| \cos(90^\circ) \end{bmatrix} = \begin{bmatrix} \cos(\theta) \\ \sin(\theta) \\ 0 \end{bmatrix}$

Attitude (Orientation)

- y_e^i:



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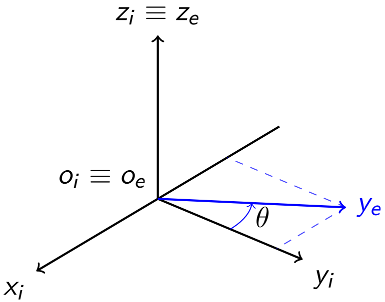
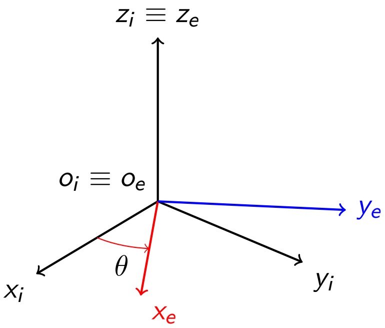


- $y_e^i = \begin{bmatrix} y_e \cdot x_i \\ y_e \cdot y_i \\ y_e \cdot z_i \end{bmatrix} = \begin{bmatrix} \|y_e\|\|x_i\| \cos(90^\circ + \theta) \\ \|y_e\|\|y_i\| \cos(\theta) \\ \|y_e\|\|z_i\| \cos(90^\circ) \end{bmatrix} = \begin{bmatrix} -\sin(\theta) \\ \cos(\theta) \\ 0 \end{bmatrix}$

- z_e^i:



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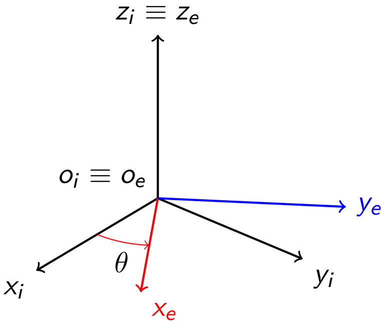

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- $C_e^i = \left[\begin{array}{c|c|c} x_e^i & y_e^i & z_e^i \end{array}\right] = \left[\begin{array}{c|c|c} \cos(\theta) & -\sin(\theta) & 0 \\ \sin(\theta) & \cos(\theta) & 0 \\ 0 & 0 & 1 \end{array}\right]$

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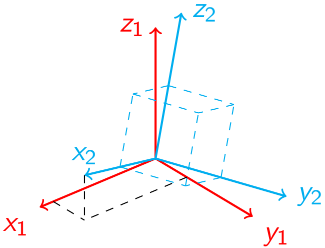
- C_e^i describes the attitude/orientation of the $e-$frame wrt the $i-$frame
- C_e^i referred to as a rotation matrix, coordinate transformation matrix, or direct cosine matrix (DCM)

- In general, a rotation matrix C_2^1 describes the orientation of frame {2} relative to frame {1}



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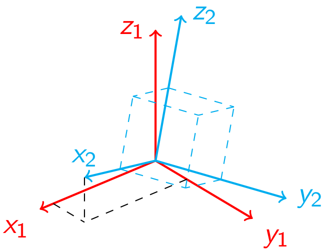

- via $C_2^1 = \left[x_2^1,\ y_2^1,\ z_2^1\right] = \begin{bmatrix} x_2 \cdot x_1, & y_2 \cdot x_1, & z_2 \cdot x_1 \\ x_2 \cdot y_1, & y_2 \cdot y_1, & z_2 \cdot y_1 \\ x_2 \cdot z_1, & y_2 \cdot z_1, & z_2 \cdot z_1 \end{bmatrix}$

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$$\begin{bmatrix} x_1 \cdot x_2, & x_1 \cdot y_2, & x_1 \cdot z_2 \\ y_1 \cdot x_2, & y_1 \cdot y_2, & y_1 \cdot z_2 \\ z_1 \cdot x_2, & z_1 \cdot y_2, & z_1 \cdot z_2 \end{bmatrix} = \begin{bmatrix} (x_1^2)^T \\ (y_1^2)^T \\ (z_1^2)^T \end{bmatrix} = \left[x_1^2,\ y_1^2,\ z_1^2\right]^T = \left[C_1^2\right]^T$$

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- opposite perspective (2 wrt 1 given 1 wrt 2) is as simple as a matrix transpose!

1. $\left[C_2^1\right]^T C_2^1 = C_1^2 C_2^1 = I \;\Rightarrow C_1^2 = \left[C_2^1\right]^T = \left[C_2^1\right]^{-1}$

Properties of Rotation Matrix

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3. columns and rows of C_2^1 are orthogonal
4. magnitude of columns and rows in C_2^1 are 1

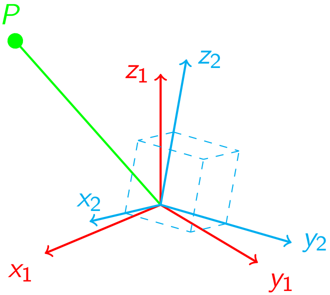
- So far, rotation matrix C developed to describe orientation

Rotation Matrix as Coordinate Transformation

- So far, rotation matrix C developed to describe orientation
- C can also perform change of coordinates on vector

- Consider a point P with location described as a vector in coordinate frame {1} as

$$\vec{P}^{\,1} = \begin{bmatrix} u \\ v \\ w \end{bmatrix} = ux_1 + vy_1 + wz_1$$



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- With $\vec{P}^{\,1}$ given, the location of point P can be described in coordinate frame {2} via

$$\vec{P}^{\,2} = \begin{bmatrix} \vec{P}^{\,1} \cdot x_2 \\ \vec{P}^{\,1} \cdot y_2 \\ \vec{P}^{\,1} \cdot z_2 \end{bmatrix} = \begin{bmatrix} (ux_1 + vy_1 + wz_1) \cdot x_2 \\ (ux_1 + vy_1 + wz_1) \cdot y_2 \\ (ux_1 + vy_1 + wz_1) \cdot z_2 \end{bmatrix}$$

$$= \underbrace{\begin{bmatrix} x_1 \cdot x_2 & y_1 \cdot x_2 & z_1 \cdot x_2 \\ x_1 \cdot y_2 & y_1 \cdot y_2 & z_1 \cdot y_2 \\ x_1 \cdot z_2 & y_1 \cdot z_2 & z_1 \cdot z_2 \end{bmatrix}}_{?} \underbrace{\begin{bmatrix} u \\ v \\ w \end{bmatrix}}_{?}$$

$$= \underbrace{\begin{bmatrix} x_1 \cdot x_2 & y_1 \cdot x_2 & z_1 \cdot x_2 \\ x_1 \cdot y_2 & y_1 \cdot y_2 & z_1 \cdot y_2 \\ x_1 \cdot z_2 & y_1 \cdot z_2 & z_1 \cdot z_2 \end{bmatrix}}_{C_1^2} \underbrace{\begin{bmatrix} u \\ v \\ w \end{bmatrix}}_{\vec{P}^1}$$

$$= C_1^2 \vec{P}^1$$

- $\Rightarrow \vec{P}^2 = C_1^2 \vec{P}^1$

$$= \underbrace{\begin{bmatrix} x_1 \cdot x_2 & y_1 \cdot x_2 & z_1 \cdot x_2 \\ x_1 \cdot y_2 & y_1 \cdot y_2 & z_1 \cdot y_2 \\ x_1 \cdot z_2 & y_1 \cdot z_2 & z_1 \cdot z_2 \end{bmatrix}}_{C_1^2} \underbrace{\begin{bmatrix} u \\ v \\ w \end{bmatrix}}_{\vec{P}^1}$$

$$= C_1^2 \vec{P}^1$$

- $\Rightarrow \vec{P}^2 = C_1^2 \vec{P}^1$
- C_1^2 re-coordinatized vector written wrt frame 1 into frame 2 by a matrix-multiplication

$$= \underbrace{\begin{bmatrix} x_1 \cdot x_2 & y_1 \cdot x_2 & z_1 \cdot x_2 \\ x_1 \cdot y_2 & y_1 \cdot y_2 & z_1 \cdot y_2 \\ x_1 \cdot z_2 & y_1 \cdot z_2 & z_1 \cdot z_2 \end{bmatrix}}_{C_1^2} \underbrace{\begin{bmatrix} u \\ v \\ w \end{bmatrix}}_{\vec{P}^1}$$

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- $\Rightarrow \vec{P}^2 = C_1^2 \vec{P}^1$
- C_1^2 re-coordinatized vector written wrt frame 1 into frame 2 by a matrix-multiplication
- superscripts and subscripts help track/denote re-coordinatization

Similarly, coordinate transformations can be performed opposite way as well

$$\vec{P}^{\,2} = C_1^2 \vec{P}^{\,1}$$

$$\Rightarrow \vec{P}^{\,1} = [C_1^2]^{-1} \vec{P}^{\,2}$$

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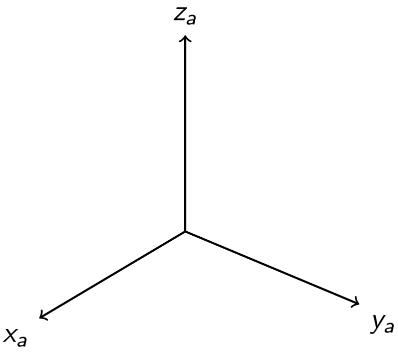
$$\Rightarrow \vec{P}^{\,1} = [C_1^2]^{-1} \vec{P}^{\,2}$$
$$= [C_1^2]^T \vec{P}^{\,2}$$
$$= C_2^1 \vec{P}^{\,2}$$

Given $C_b^a = \begin{bmatrix} 0.866 & 0 & 0.5 \\ 0.433 & 0.5 & -0.75 \\ -0.25 & 0.866 & 0.4330 \end{bmatrix}$ and frame a, sketch frame b.



Frame 1 has been rotated away from frame 0 by 30° about z_0. Find $\vec{r}^0$ given $\vec{r}^1 = [0,\ 2,\ 0]^T$.

Rotation matrix can be thought of in three distinct ways:

1. It describes the orientation of one coordinate frame *wrt* another coordinate frame
2. It represents a coordinate transformation relating the coordinates of a point (e.g., P) or vector in two different frames of reference
3. It is an operator taking a vector $\vec{p}$ and rotating it into a new vector $C\vec{p}$, both in the same system

The End