

Aerospace Toolbox

User's Guide



MATLAB[®]

R2021a



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Aerospace Toolbox User's Guide

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Revision History

September 2006	Online only	New for Version 1.0 (Release 2006b)
March 2007	Online only	Revised for Version 1.1 (Release 2007a)
September 2007	First printing	Revised for Version 2.0 (Release 2007b)
March 2008	Online only	Revised for Version 2.1 (Release 2008a)
October 2008	Online only	Revised for Version 2.2 (Release 2008b)
March 2009	Online only	Revised for Version 2.3 (Release 2009a)
September 2009	Online only	Revised for Version 2.4 (Release 2009b)
March 2010	Online only	Revised for Version 2.5 (Release 2010a)
September 2010	Online only	Revised for Version 2.6 (Release 2010b)
April 2011	Online only	Revised for Version 2.7 (Release 2011a)
September 2011	Online only	Revised for Version 2.8 (Release 2011b)
March 2012	Online only	Revised for Version 2.9 (Release 2012a)
September 2012	Online only	Revised for Version 2.10 (Release 2012b)
March 2013	Online only	Revised for Version 2.11 (Release 2013a)
September 2013	Online only	Revised for Version 2.12 (Release 2013b)
March 2014	Online only	Revised for Version 2.13 (Release 2014a)
October 2014	Online only	Revised for Version 2.14 (Release 2014b)
March 2015	Online only	Revised for Version 2.15 (Release 2015a)
September 2015	Online only	Revised for Version 2.16 (Release 2015b)
March 2016	Online only	Revised for Version 2.17 (Release 2016a)
September 2016	Online only	Revised for Version 2.18 (Release 2016b)
March 2017	Online only	Revised for Version 2.19 (Release 2017a)
September 2017	Online only	Revised for Version 2.20 (Release 2017b)
March 2018	Online only	Revised for Version 2.21 (Release 2018a)
September 2018	Online only	Revised for Version 3.0 (Release 2018b)
March 2019	Online only	Revised for Version 3.1 (Release 2019a)
September 2019	Online only	Revised for Version 3.2 (Release 2019b)
March 2020	Online only	Revised for Version 3.3 (Release 2020a)
September 2020	Online only	Revised for Version 3.4 (Release 2020b)
March 2021	Online only	Revised for Version 4.0 (Release 2021a)

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Getting Started

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- “Aerospace Toolbox and Aerospace Blockset” on page 1-3

Aerospace Toolbox Product Description

Analyze and visualize aerospace vehicle motion using reference standards and models

Aerospace Toolbox provides standards-based tools and functions for analyzing the motion, mission, and environment of aerospace vehicles. It includes aerospace math operations, coordinate system and spatial transformations, and validated environment models for interpreting flight data. The toolbox also includes 2D and 3D visualization tools and standard cockpit instruments for observing vehicle motion.

For flight vehicles, you can import Data Compendium (Datcom) files directly into MATLAB® to represent vehicle aerodynamics. The aerodynamics can be combined with reference parameters to define your aircraft configuration and dynamics for control design and flying qualities analysis.

Aerospace Toolbox lets you design and analyze scenarios consisting of satellites and ground stations. You can propagate satellite trajectories from orbital elements or two-line element sets, load in satellite and constellation ephemerides, perform mission analysis tasks such as line-of-sight access, and visualize the scenario as a ground track or globe.

Aerospace Toolbox and Aerospace Blockset

The Aerospace product family includes the Aerospace Toolbox and Aerospace Blockset products. The toolbox provides static data analysis capabilities, while the blockset provides an environment for dynamic modeling and vehicle component modeling and simulation. The Aerospace Blockset software uses part of the functionality of the toolbox as an engine. Use these products together to model aerospace systems in the MATLAB and Simulink® environments.

Using Aerospace Toolbox

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Fundamental Coordinate System Concepts

Coordinate systems allow you to track an aircraft or spacecraft position and orientation in space. The Aerospace Toolbox coordinate systems are based on these underlying concepts from geodesy, astronomy, and physics.

Definitions

The Aerospace Toolbox software uses right-handed (RH) Cartesian coordinate systems. The rightmost rule establishes the x - y - z sequence of coordinate axes.

An inertial frame is a nonaccelerating motion reference frame. Loosely speaking, acceleration is defined with respect to the distant cosmos. In an inertial frame, Newton's second law (force = mass X acceleration) holds.

Strictly defined, an inertial frame is a member of the set of all frames not accelerating relative to one another. A noninertial frame is any frame accelerating relative to an inertial frame. Its acceleration, in general, includes both translational and rotational components, resulting in pseudoforces (pseudogravity, as well as Coriolis and centrifugal forces).

The toolbox models the Earth shape (the geoid) as an oblate spheroid, a special type of ellipsoid with two longer axes equal (defining the equatorial plane) and a third, slightly shorter (geopolar) axis of symmetry. The equator is the intersection of the equatorial plane and the Earth surface. The geographic poles are the intersection of the Earth surface and the geopolar axis. In general, the Earth geopolar and rotation axes are not identical.

Latitudes parallel the equator. Longitudes parallel the geopolar axis. The zero longitude or prime meridian passes through Greenwich, England.

Approximations

The Aerospace Toolbox software makes three standard approximations in defining coordinate systems relative to the Earth.

- The Earth surface or geoid is an oblate spheroid, defined by its longer equatorial and shorter geopolar axes. In reality, the Earth is slightly deformed with respect to the standard geoid.
- The Earth rotation axis and equatorial plane are perpendicular, so that the rotation and geopolar axes are identical. In reality, these axes are slightly misaligned, and the equatorial plane wobbles as the Earth rotates. This effect is negligible in most applications.
- The only noninertial effect in Earth-fixed coordinates is due to the Earth rotation about its axis. This is a *rotating, geocentric* system. The toolbox ignores the Earth motion around the Sun, the Sun motion in the Galaxy, and the Galaxy's motion through cosmos. In most applications, only the Earth rotation matters.

This approximation must be changed for spacecraft sent into deep space, that is, outside the Earth-Moon system, and a heliocentric system is preferred.

Motion with Respect to Other Planets

The Aerospace Toolbox software uses the standard WGS-84 geoid to model the Earth. You can change the equatorial axis length, the flattening, and the rotation rate.

You can represent the motion of spacecraft with respect to any celestial body that is well approximated by an oblate spheroid by changing the spheroid size, flattening, and rotation rate. If the celestial body is rotating westward (retrogradely), make the rotation rate negative.

References

Recommended Practice for Atmospheric and Space Flight Vehicle Coordinate Systems, R-004-1992, ANSI/AIAA, February 1992.

Mapping Toolbox™ documentation, The MathWorks, Inc., Natick, Massachusetts. “Mapping Toolbox”.

Rogers, R. M., *Applied Mathematics in Integrated Navigation Systems*, AIAA, Reston, Virginia, 2000.

Stevens, B. L., and F. L. Lewis, *Aircraft Control, and Simulation*, 2nd ed., Wiley-Interscience, New York, 2003.

Thomson, W. T., *Introduction to Space Dynamics*, John Wiley & Sons, New York, 1961/Dover Publications, Mineola, New York, 1986.

World Geodetic System 1984 (WGS 84), <https://earth-info.nga.mil/GandG/update/index.php>.

Coordinate Systems for Modeling

Modeling aircraft and spacecraft are simplest if you use a coordinate system fixed in the body itself. In the case of aircraft, the forward direction is modified by the presence of wind, and the craft's motion through the air is not the same as its motion relative to the ground.

Body Coordinates

The noninertial body coordinate system is fixed in both origin and orientation to the moving craft. The craft is assumed to be rigid.

The orientation of the body coordinate axes is fixed in the shape of body.

- The x -axis points through the nose of the craft.
- The y -axis points to the right of the x -axis (facing in the pilot's direction of view), perpendicular to the x -axis.
- The z -axis points down through the bottom of the craft, perpendicular to the x - y plane and satisfying the RH rule.

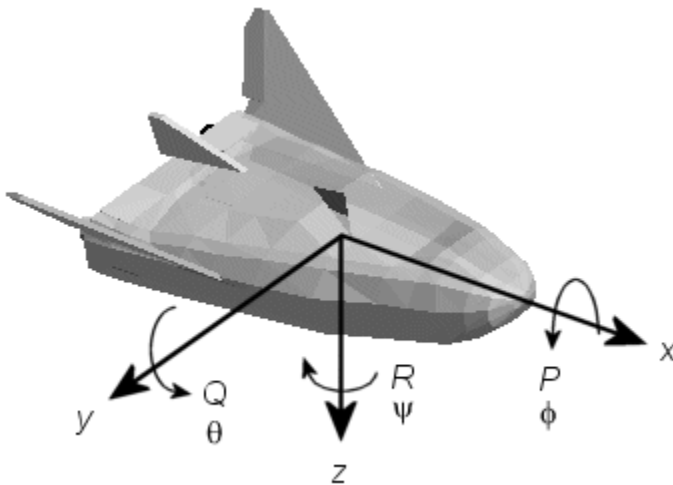
Translational Degrees of Freedom

Translations are defined by moving along these axes by distances x , y , and z from the origin.

Rotational Degrees of Freedom

Rotations are defined by the Euler angles P , Q , R or Φ , Θ , Ψ . They are

- P or Φ : Roll about the x -axis
- Q or Θ : Pitch about the y -axis
- R or Ψ : Yaw about the z -axis



Unless otherwise specified, by default the software uses ZYX rotation order for Euler angles.

Wind Coordinates

The noninertial wind coordinate system has its origin fixed in the rigid aircraft. The coordinate system orientation is defined relative to the craft's velocity V .

The orientation of the wind coordinate axes is fixed by the velocity V .

- The x -axis points in the direction of V .
- The y -axis points to the right of the x -axis (facing in the direction of V), perpendicular to the x -axis.
- The z -axis points perpendicular to the x - y plane in whatever way needed to satisfy the RH rule with respect to the x - and y -axes.

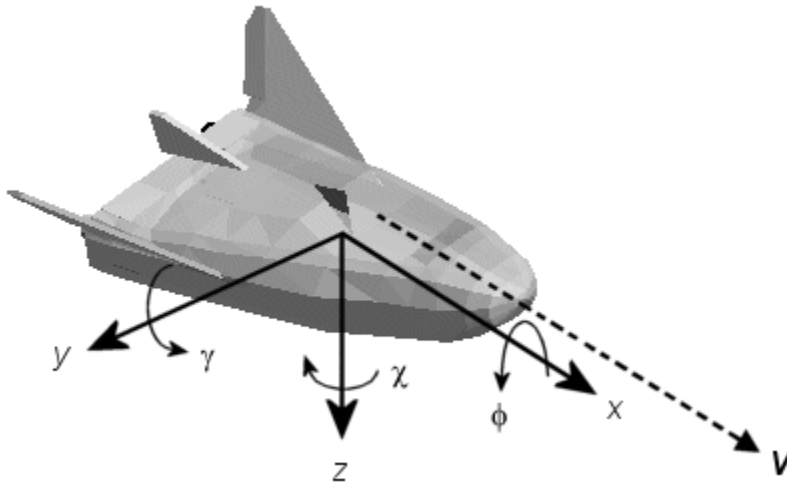
Translational Degrees of Freedom

Translations are defined by moving along these axes by distances x , y , and z from the origin.

Rotational Degrees of Freedom

Rotations are defined by the Euler angles Φ , γ , χ . They are

- Φ : Bank angle about the x -axis
- γ : Flight path about the y -axis
- χ : Heading angle about the z -axis



Unless otherwise specified, by default the software uses ZYX rotation order for Euler angles.

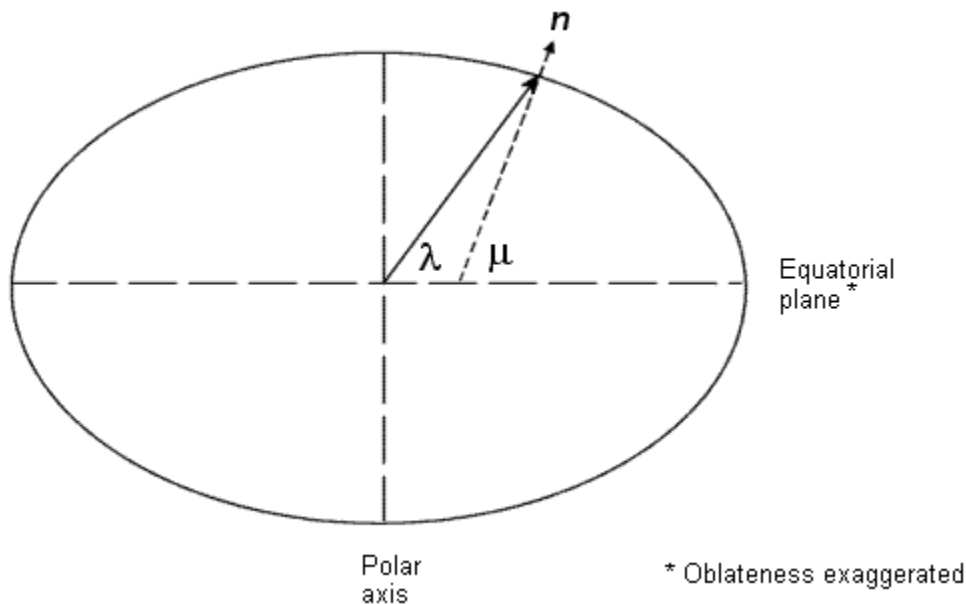
Coordinate Systems for Navigation

Modeling aerospace trajectories requires positioning and orienting the aircraft or spacecraft with respect to the rotating Earth. Navigation coordinates are defined with respect to the center and surface of the Earth.

Geocentric and Geodetic Latitudes

The geocentric latitude λ on the Earth surface is defined by the angle subtended by the radius vector from the Earth center to the surface point with the equatorial plane.

The geodetic latitude μ on the Earth surface is defined by the angle subtended by the surface normal vector n and the equatorial plane.

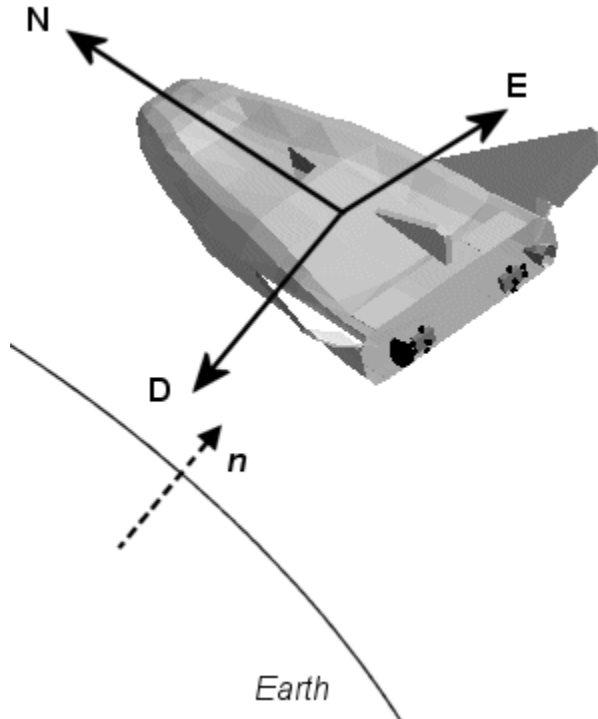


NED Coordinates

The north-east-down (NED) system is a noninertial system with its origin fixed at the aircraft or spacecraft's center of gravity. Its axes are oriented along the geodetic directions defined by the Earth surface.

- The x -axis points north parallel to the geoid surface, in the polar direction.
- The y -axis points east parallel to the geoid surface, along a latitude curve.
- The z -axis points downward, toward the Earth surface, antiparallel to the surface's outward normal n .

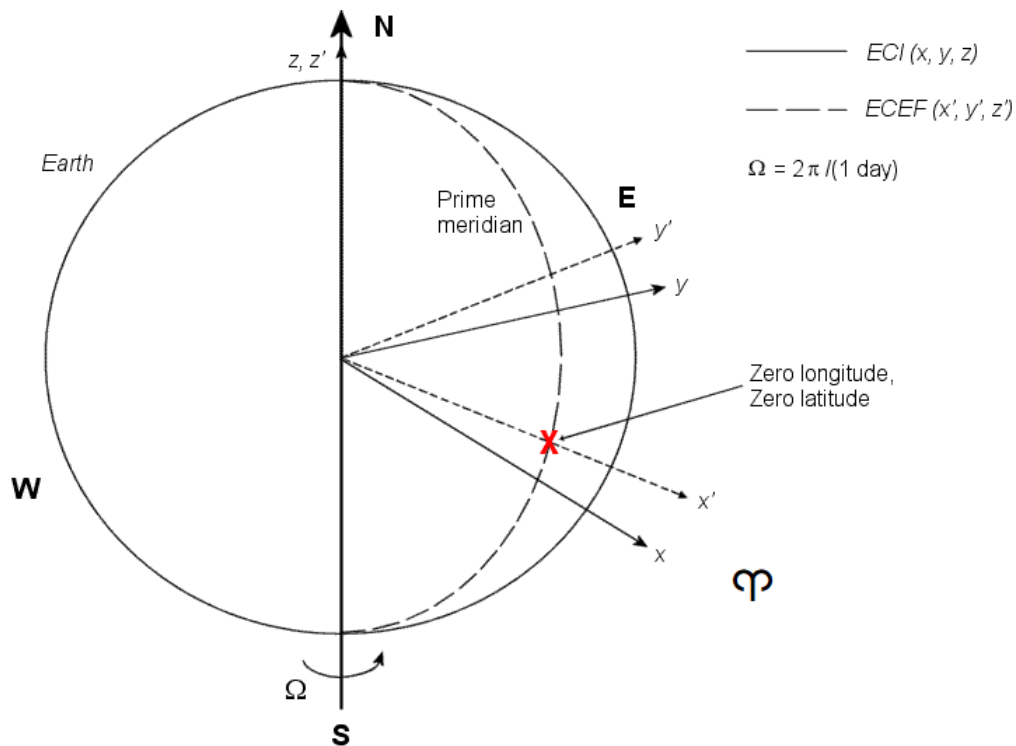
Flying at a constant altitude means flying at a constant z above the Earth's surface.



ECI Coordinates

The Earth-centered inertial (ECI) system is non-rotating. For most applications, assume this frame to be inertial, although the equinox and equatorial plane move very slightly over time. The ECI system is considered to be truly inertial for high-precision orbit calculations when the equator and equinox are defined at a particular epoch (e.g. J2000). Aerospace functions and blocks that use a particular realization of the ECI coordinate system provide that information in their documentation. The ECI system origin is fixed at the center of the Earth (see figure).

- The x -axis points towards the vernal equinox (First Point of Aries Υ).
- The y -axis points 90 degrees to the east of the x -axis in the equatorial plane.
- The z -axis points northward along the Earth rotation axis.



Earth-Centered Coordinates

ECEF Coordinates

The Earth-center, Earth-fixed (ECEF) system is a noninertial system that rotates with the Earth. Its origin is fixed at the center of the Earth.

- The z -axis points northward along the Earth's rotation axis.
- The x -axis points outward along the intersection of the Earth's equatorial plane and prime meridian.
- The y -axis points into the eastward quadrant, perpendicular to the x - z plane so as to satisfy the RH rule.

Coordinate Systems for Display

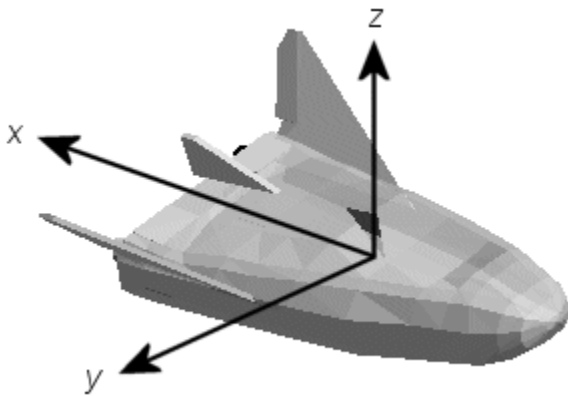
The Aerospace Toolbox software lets you use FlightGear coordinates for rendering motion.

FlightGear is an open-source, third-party flight simulator with an interface supported by the Aerospace Toolbox product.

- “Flight Simulator Interface Example” on page 2-42 discusses the toolbox interface to FlightGear.
- See the FlightGear documentation at www.flightgear.org for complete information about this flight simulator.

The FlightGear coordinates form a special body-fixed system, rotated from the standard body coordinate system about the y -axis by -180 degrees:

- The x -axis is positive toward the back of the vehicle.
- The y -axis is positive toward the right of the vehicle.
- The z -axis is positive upward, e.g., wheels typically have the lowest z values.



Aerospace Units

The Aerospace Toolbox functions support standard measurement systems. The Unit Conversion functions provide means for converting common measurement units from one system to another, such as converting velocity from feet per second to meters per second and vice versa.

The unit conversion functions support all units listed in this table.

Quantity	MKS (SI)	English
Acceleration	meters/second ² (m/s ²), kilometers/second ² (km/s ²), (kilometers/hour)/second (km/h-s), g-unit (<i>g</i>)	inches/second ² (in/s ²), feet/second ² (ft/s ²), (miles/hour)/second (mph/s), g-unit (<i>g</i>)
Angle	radian (rad), degree (deg), revolution	radian (rad), degree (deg), revolution
Angular acceleration	radians/second ² (rad/s ²), degrees/second ² (deg/s ²)	radians/second ² (rad/s ²), degrees/second ² (deg/s ²)
Angular velocity	radians/second (rad/s), degrees/second (deg/s), revolutions/minute (rpm), revolutions/second (rps)	radians/second (rad/s), degrees/second (deg/s), revolutions/minute (rpm), revolutions/second (rps)
Density	kilogram/meter ³ (kg/m ³)	pound mass/foot ³ (lbm/ft ³), slug/foot ³ (slug/ft ³), pound mass/inch ³ (lbm/in ³)
Force	newton (N)	pound (lb)
Length	meter (m)	inch (in), foot (ft), mile (mi), nautical mile (nm)
Mass	kilogram (kg)	slug (slug), pound mass (lbm)
Pressure	pascal (Pa)	pound/inch ² (psi), pound/foot ² (psf), atmosphere (atm)
Temperature	kelvin (K), degrees Celsius (°C)	degrees Fahrenheit (°F), degrees Rankine (°R)
Velocity	meters/second (m/s), kilometers/second (km/s), kilometers/hour (km/h)	inches/second (in/sec), feet/second (ft/sec), feet/minute (ft/min), miles/hour (mph), knots

Digital DATCOM Data

In this section...

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“USAF Digital DATCOM File” on page 2-11

“Data from DATCOM Files” on page 2-11

“Imported DATCOM Data” on page 2-12

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“Aerodynamic Coefficients” on page 2-15

Digital DATCOM Data Overview

The Aerospace Toolbox product enables bringing United States Air Force (USAF) Digital DATCOM files into the MATLAB environment by using the `datcomimport` function. For more information, see the `datcomimport` function reference page. This section explains how to import data from a USAF Digital DATCOM file.

The example used in the following topics is available as an Aerospace Toolbox example. You can run the example by entering `astimportddatcom` in the MATLAB Command Window.

USAF Digital DATCOM File

The following is a sample input file for USAF Digital DATCOM for a wing-body-horizontal tail-vertical tail configuration running over five alphas, two Mach numbers, and two altitudes and calculating static and dynamic derivatives. You can also view this file by entering `type astdatcom.in` in the MATLAB Command Window.

```
$FLTCN NMACH=2.0,MACH(1)=0.1,0.2$
$FLTCN NALT=2.0,ALT(1)=5000.0,8000.0$
$FLTCN NALPHA=5.,ALSCHD(1)=-2.0,0.0,2.0,
ALSCHD(4)=4.0,8.0,LOOP=2.0$
$OPTINS SREF=225.8,CBARR=5.75,BLREF=41.15$
$SYNTHS XCG=7.08,ZCG=0.0,XW=6.1,ZW=-1.4,ALIW=1.1,XH=20.2,
ZH=0.4,ALIH=0.0,XV=21.3,ZV=0.0,VERTUP=.TRUE.$
$BODY NX=10.0,
X(1)=-4.9,0.0,3.0,6.1,9.1,13.3,20.2,23.5,25.9,
R(1)=0.0,1.0,1.75,2.6,2.6,2.6,2.0,1.0,0.0$
$WGPLNF CHRDT=4.0,SSPNE=18.7,SSPN=20.6,CHRDR=7.2,SAVSI=0.0,CHSTAT=0.25,
TWISTA=-1.1,SSPND=0.0,DHDADI=3.0,DHDADO=3.0,TYPE=1.0$
NACA-W-6-64A412
$HTPLNF CHRDT=2.3,SSPNE=5.7,SSPN=6.625,CHRDR=0.25,SAVSI=11.0,
CHSTAT=1.0,TWISTA=0.0,TYPE=1.0$
NACA-H-4-0012
$VTPLNF CHRDT=2.7,SSPNE=5.0,SSPN=5.2,CHRDR=5.3,SAVSI=31.3,
CHSTAT=0.25,TWISTA=0.0,TYPE=1.0$
NACA-V-4-0012
CASEID SKYHOGG BODY-WING-HORIZONTAL TAIL-VERTICAL TAIL CONFIG
DAMP
NEXT CASE
```

The output file generated by USAF Digital DATCOM for the same wing-body-horizontal tail-vertical tail configuration running over five alphas, two Mach numbers, and two altitudes can be viewed by entering `type astdatcom.out` in the MATLAB Command Window.

Data from DATCOM Files

Use the `datcomimport` function to bring the Digital DATCOM data into the MATLAB environment.

```
alldata = datcomimport('astdatcom.out', true, 0);
```

Imported DATCOM Data

The `datcomimport` function creates a cell array of structures containing the data from the Digital DATCOM output file.

```
data = alldata{1}
data =
  struct with fields:
    case: 'SKYHOGG BODY-WING-HORIZONTAL TAIL-VERTICAL TAIL CONFIG'
    mach: [0.1000 0.2000]
      alt: [5000 8000]
    alpha: [-2 0 2 4 8]
    nmach: 2
      nalt: 2
    nalpha: 5
    rnnub: []
    hypers: 0
      loop: 2
      sref: 225.8000
      cbar: 5.7500
      blref: 41.1500
      dim: 'ft'
      deriv: 'deg'
      stmach: 0.6000
      tsmach: 1.4000
      save: 0
      stype: []
      trim: 0
      damp: 1
      build: 1
      part: 0
    highsym: 0
    highasy: 0
    highcon: 0
      tjet: 0
    hypeff: 0
      lb: 0
      pwr: 0
      grnd: 0
    wsspn: 18.7000
    hsspn: 5.7000
    ndelta: 0
    delta: []
    deltal: []
    deltar: []
      ngh: 0
    grndht: []
    config: [1x1 struct]
      cd: [5x2x2 double]
      cl: [5x2x2 double]
      cm: [5x2x2 double]
      cn: [5x2x2 double]
      ca: [5x2x2 double]
      xcp: [5x2x2 double]
      cla: [5x2x2 double]
      cma: [5x2x2 double]
      cyb: [5x2x2 double]
      cnb: [5x2x2 double]
      clb: [5x2x2 double]
      qqinf: [5x2x2 double]
      eps: [5x2x2 double]
    depsdalp: [5x2x2 double]
      clq: [5x2x2 double]
      cmq: [5x2x2 double]
      clad: [5x2x2 double]
      cmad: [5x2x2 double]
      clp: [5x2x2 double]
      cyp: [5x2x2 double]
      cnp: [5x2x2 double]
      cnr: [5x2x2 double]
      clr: [5x2x2 double]
```

Missing DATCOM Data

By default, missing data points are set to 99999 and data points are set to NaN where no DATCOM methods exist or where the method is not applicable.

It can be seen in the Digital DATCOM output file and examining the imported data that $C_{Y\beta}$, $C_{n\beta}$, C_{Lq} , and C_{mq} have data only in the first alpha value. Here are the imported data values.

```
data.cyb
ans(:,:,1) =
    1.0e+004 *
    -0.0000    -0.0000
     9.9999     9.9999
     9.9999     9.9999
     9.9999     9.9999
     9.9999     9.9999
```

```
ans(:,:,2) =
    1.0e+004 *
    -0.0000    -0.0000
     9.9999     9.9999
     9.9999     9.9999
     9.9999     9.9999
     9.9999     9.9999
```

```
data.cnb
ans(:,:,1) =
    1.0e+004 *
     0.0000     0.0000
     9.9999     9.9999
     9.9999     9.9999
     9.9999     9.9999
     9.9999     9.9999
```

```
ans(:,:,2) =
    1.0e+004 *
     0.0000     0.0000
     9.9999     9.9999
     9.9999     9.9999
     9.9999     9.9999
     9.9999     9.9999
```

```
data.clq
ans(:,:,1) =
    1.0e+004 *
     0.0000     0.0000
     9.9999     9.9999
     9.9999     9.9999
     9.9999     9.9999
     9.9999     9.9999
```

```
ans(:,:,2) =
    1.0e+004 *
     0.0000     0.0000
     9.9999     9.9999
     9.9999     9.9999
     9.9999     9.9999
     9.9999     9.9999
```

```
data.cmq
ans(:,:,1) =
```

```

1.0e+004 *
-0.0000 -0.0000
 9.9999  9.9999
 9.9999  9.9999
 9.9999  9.9999
 9.9999  9.9999

ans(:,:,2) =

1.0e+004 *
-0.0000 -0.0000
 9.9999  9.9999
 9.9999  9.9999
 9.9999  9.9999
 9.9999  9.9999

```

The missing data points will be filled with the values for the first alpha, since these data points are meant to be used for all alpha values.

```

aerotab = {'cyb' 'cnb' 'clq' 'cmq'};

for k = 1:length(aerotab)
    for m = 1:data.nmach
        for h = 1:data.nalt
            data.(aerotab{k})(:,m,h) = data.(aerotab{k})(1,m,h);
        end
    end
end
end

```

Here are the updated imported data values.

```

data.cyb
ans(:,:,1) =

-0.0035 -0.0035
-0.0035 -0.0035
-0.0035 -0.0035
-0.0035 -0.0035
-0.0035 -0.0035

ans(:,:,2) =

-0.0035 -0.0035
-0.0035 -0.0035
-0.0035 -0.0035
-0.0035 -0.0035
-0.0035 -0.0035

data.cnb
ans(:,:,1) =

1.0e-003 *

 0.9142  0.8781
 0.9142  0.8781
 0.9142  0.8781
 0.9142  0.8781
 0.9142  0.8781

ans(:,:,2) =

1.0e-003 *

 0.9190  0.8829
 0.9190  0.8829
 0.9190  0.8829
 0.9190  0.8829
 0.9190  0.8829

data.clq
ans(:,:,1) =

 0.0974  0.0984
 0.0974  0.0984
 0.0974  0.0984

```

```

0.0974    0.0984
0.0974    0.0984

```

```
ans(:,:,2) =
```

```

0.0974    0.0984
0.0974    0.0984
0.0974    0.0984
0.0974    0.0984
0.0974    0.0984

```

```
data.cmq
ans(:,:,1) =
```

```

-0.0892   -0.0899
-0.0892   -0.0899
-0.0892   -0.0899
-0.0892   -0.0899
-0.0892   -0.0899

```

```
ans(:,:,2) =
```

```

-0.0892   -0.0899
-0.0892   -0.0899
-0.0892   -0.0899
-0.0892   -0.0899
-0.0892   -0.0899

```

Aerodynamic Coefficients

You can now plot the aerodynamic coefficients:

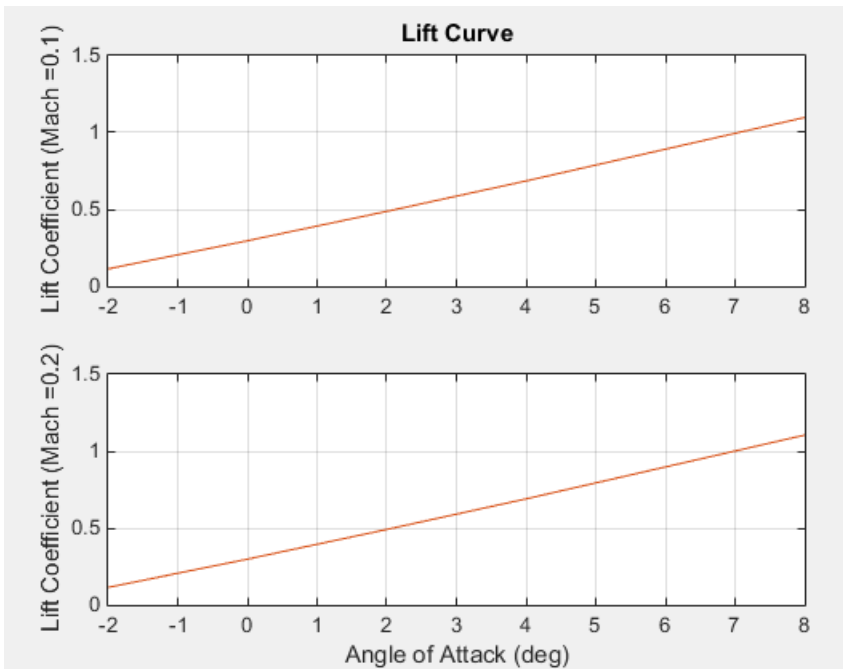
- “Plotting Lift Curve Moments” on page 2-15
- “Plotting Drag Polar Moments” on page 2-16
- “Plotting Pitching Moments” on page 2-17

Plotting Lift Curve Moments

```

h1 = figure;
figtitle = {'Lift Curve' ''};
for k=1:2
    subplot(2,1,k)
    plot(data.alpha,permute(data.cl(:,k,:),[1 3 2]))
    grid
    ylabel(['Lift Coefficient (Mach = ' num2str(data.mach(k)) ' '])
    title(figtitle{k});
end
xlabel('Angle of Attack (deg)')

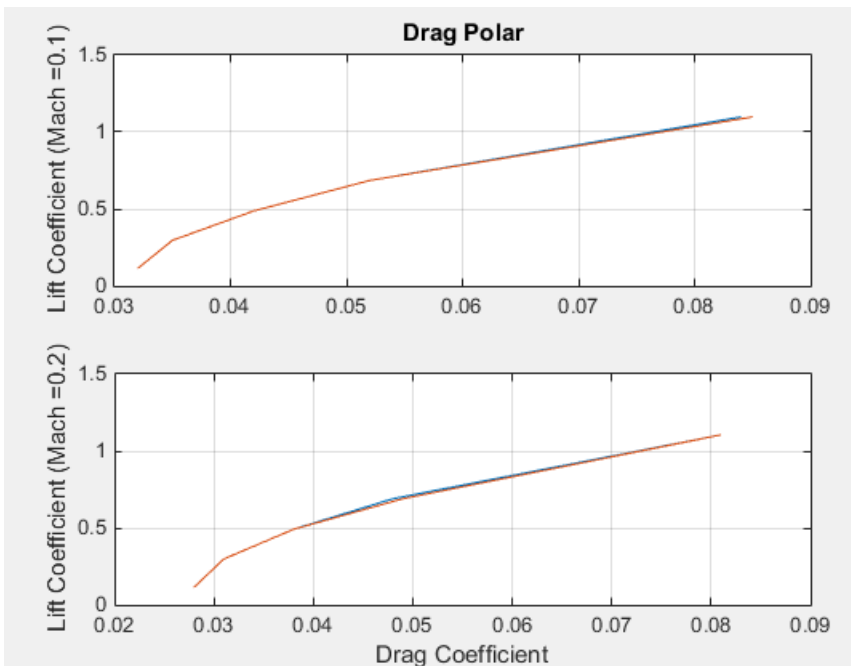
```



Plotting Drag Polar Moments

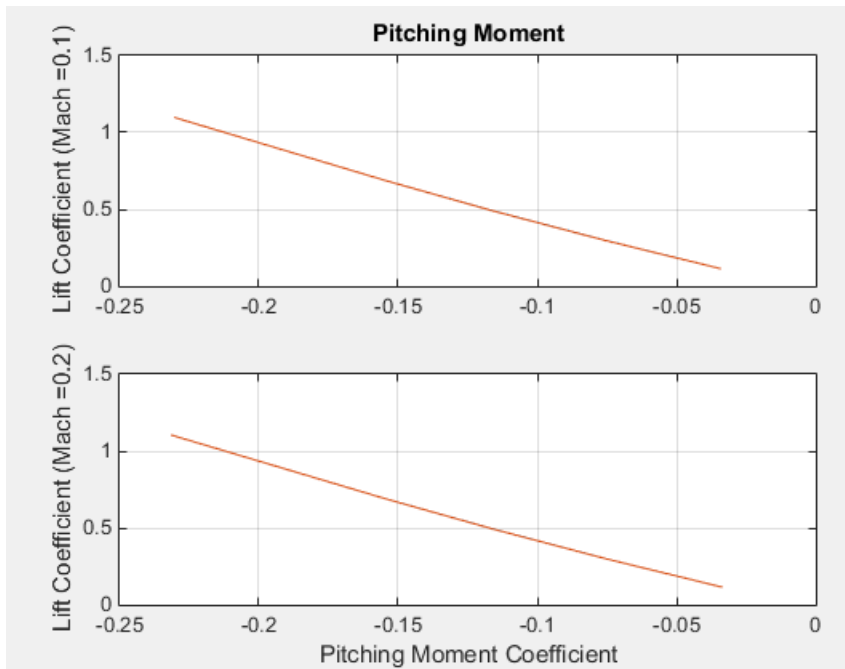
```

h2 = figure;
figtitle = {'Drag Polar' ''};
for k=1:2
    subplot(2,1,k)
    plot(permute(data.cd(:,k,:),[1 3 2]),permute(data.cl(:,k,:),[1 3 2]))
    grid
    ylabel(['Lift Coefficient (Mach = ' num2str(data.mach(k)) ' ')'])
    title(figtitle{k})
end
xlabel('Drag Coefficient')
    
```



Plotting Pitching Moments

```
h3 = figure;  
figtitle = {'Pitching Moment' ''};  
for k=1:2  
    subplot(2,1,k)  
    plot(permute(data.cm(:,k,:),[1 3 2]),permute(data.cl(:,k,:),[1 3 2]))  
    grid  
    ylabel(['Lift Coefficient (Mach = ' num2str(data.mach(k)) ' ')]  
    title(figtitle{k})  
end  
xlabel('Pitching Moment Coefficient')
```



Aerospace Toolbox Animation Objects

To visualize flight data in the Aerospace Toolbox environment, you can use the following animation objects and their associated methods. These animation objects use the MATLAB time series object, `timeseries` to visualize flight data.

- `Aero.Animation` — Visualize flight data without any other tool or toolbox. The following objects support this object.
 - `Aero.Body`
 - `Aero.Camera`
 - `Aero.Geometry`

For more information, see “`Aero.Animation Objects`” on page 2-19.

- `Aero.VirtualRealityAnimation` — Visualize flight data with the Simulink 3D Animation™ product. The following objects support this object.
 - `Aero.Node`
 - `Aero.Viewpoint`

For more information, see “`Aero.VirtualRealityAnimation Objects`” on page 2-27.

- `Aero.FlightGearAnimation` — Visualize flight data with the FlightGear simulator. For more information, see “`Aero.FlightGearAnimation Objects`” on page 2-40.

Aero.Animation Objects

The toolbox interface to animation objects uses the Handle Graphics capability. The Overlaying Simulated and Actual Flight Data (`astmlanim`) example visually compares simulated and actual flight trajectory data by creating animation objects, creating bodies for those objects, and loading the flight trajectory data.

- Create and configure an animation object.
- Load recorded data for flight trajectories.
- Display body geometries in a figure window.
- Play back flight trajectories using the animation object.
- Manipulate the camera.
- Move and reposition bodies.
- Create a transparency in the first body.
- Change the color of the second body.
- Turn off the landing gear of the second body.

Running the Example

- 1 Start the MATLAB software.
- 2 Enter `astmlanim` in the MATLAB Command Window.

While running, the example performs several steps by issuing a series of commands.

Simulated and Actual Flight Data Using Aero.Animation Objects

Creating and Configuring an Animation Object

This series of commands creates an animation object and configures the object.

- 1 Create an animation object.

```
h = Aero.Animation;
```

- 2 Configure the animation object to set the number of frames per second (`FramesPerSecond`) property. This configuration controls the rate at which frames are displayed in the figure window.

```
h.FramesPerSecond = 10;
```

- 3 Configure the animation object to set the seconds of animation data per second time scaling (`TimeScaling`) property.

```
h.TimeScaling = 5;
```

The combination of `FramesPerSecond` and `TimeScaling` property determine the time step of the simulation. These settings result in a time step of approximately 0.5 s.

- 4 Create and load bodies for the animation object. This example uses these bodies to work with and display the simulated and actual flight trajectories. The first body is orange; it represents simulated data. The second body is blue; it represents the actual flight data.

```
idx1 = h.createBody('pa24-250_orange.ac', 'Ac3d');  
idx2 = h.createBody('pa24-250_blue.ac', 'Ac3d');
```

Both bodies are AC3D format files. AC3D is one of several file formats that the animation objects support. FlightGear uses the same file format. The animation object reads in the bodies in the AC3D format and stores them as patches in the geometry object within the animation object.

Loading Recorded Data for Flight Trajectories

This series of commands loads the recorded flight trajectory data, which is contained in files in the `matlabroot\toolbox\aero\astdemos` folder.

- `simdata` - Contains simulated flight trajectory data, which is set up as a 6DoF array.
- `fltdata` - Contains actual flight trajectory data which is set up in a custom format. To access this custom format data, the example must set the body object **TimeSeriesSourceType** parameter to `Custom` and then specify a custom read function.

- 1 Load the flight trajectory data.

```
load simdata  
load fltdata
```

- 2 Set the time series data for the two bodies.

```
h.Bodies{1}.TimeSeriesSource = simdata;  
h.Bodies{2}.TimeSeriesSource = fltdata;
```

- 3 Identify the time series for the second body as custom.

```
h.Bodies{2}.TimeSeriesSourceType = 'Custom';
```

- 4 Specify the custom read function to access the data in `fltdata` for the second body. The example provides the custom read function in `matlabroot\toolbox\ aero\astdemos\CustomReadBodyTSDData.m`.

```
h.Bodies{2}.TimeseriesReadFcn = @CustomReadBodyTSDData;
```

Displaying Body Geometries in a Figure Window

This command creates a figure object for the animation object.

```
h.show();
```

Recording Animation Files

Enable recording of the playback of flight trajectories using the animation object on page 2-21.

```
h.VideoRecord = 'on';  
h.VideoQuality = 50;  
h.VideoCompression = 'Motion JPEG AVI'  
h.VideoFilename = 'astMotion_JPEG';
```

Enable animation recording at any point that you want to preserve an animation sequence.

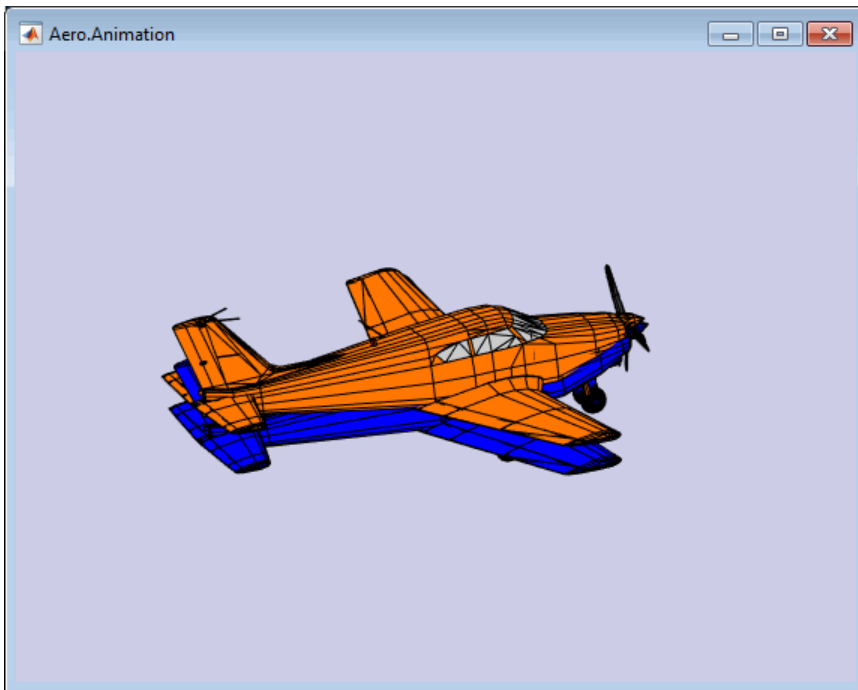
Note When choosing the video compression type, keep in mind that you will need the corresponding viewer software. For example, if you create an AVI format, you need a viewer such as Windows Media® Player to view the file.

After you play the animation as described in “Playing Back Flight Trajectories Using the Animation Object” on page 2-21, `astMotion_JPEG` contains a recording of the playback.

Playing Back Flight Trajectories Using the Animation Object

This command plays back the animation bodies for the duration of the time series data. This playback shows the differences between the simulated and actual flight data.

```
h.play();
```



If you used the Video properties to store the recording, see “Viewing Recorded Animation Files” on page 2-22 for a description of how to view the files.

Viewing Recorded Animation Files

If you do not have an animation file to view, see “Recording Animation Files” on page 2-21.

- 1 Open the folder that contains the animation file you want to view.
- 2 View the animation file with an application of your choice.

If your animation file is not yet running, start it now from the application.

- 3 To prevent other `h.play` commands from overwriting the contents of the animation file, disable the recording after you are satisfied with the contents.

```
h.VideoRecord = 'off';
```

Manipulating the Camera

This command series shows how you can manipulate the camera on the two bodies and redisplay the animation. The `PositionFcn` property of a camera object controls the camera position relative to the bodies in the animation. In “Playing Back Flight Trajectories Using the Animation Object” on page 2-21, the camera object uses a default value for the `PositionFcn` property. In this command series, the example references a custom `PositionFcn` function that uses a static position based on the position of the bodies. No dynamics are involved.

Note The custom `PositionFcn` function is located in the `matlabroot\toolbox\aero\astdemos` folder.

- 1 Set the camera `PositionFcn` to the custom function `staticCameraPosition`.

```
h.Camera.PositionFcn = @staticCameraPosition;
```

- 2 Run the animation again.

```
h.play();
```

Moving and Repositioning Bodies

This series of commands illustrates how to move and reposition bodies.

- 1 Set the starting time to 0.

```
t = 0;
```

- 2 Move the body to the starting position that is based on the time series data. Use the `Aero.Animation` object `updateBodies` method.

```
h.updateBodies(t);
```

- 3 Update the camera position using the custom `PositionFcn` function set in the previous section. Use the `Aero.Animation` object `updateCamera` method.

```
h.updateCamera(t);
```

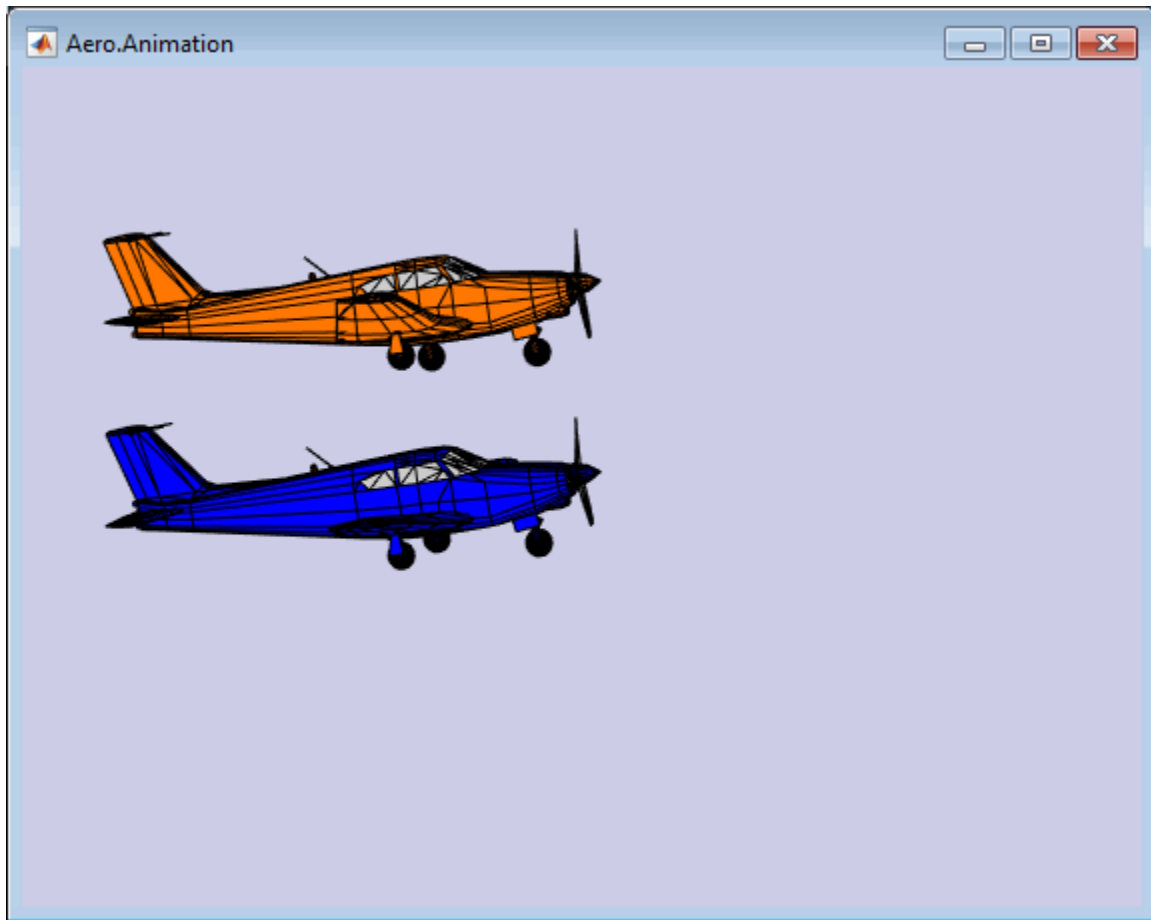
- 4 Reposition the bodies by first getting the current body position, then separating the bodies.

- a Get the current body positions and rotations from the objects of both bodies.

```
pos1 = h.Bodies{1}.Position;  
rot1 = h.Bodies{1}.Rotation;  
pos2 = h.Bodies{2}.Position;  
rot2 = h.Bodies{2}.Rotation;
```

- b Separate and reposition the bodies by moving them to new positions.

```
h.moveBody(1, pos1 + [0 0 -3], rot1);  
h.moveBody(2, pos1 + [0 0 0], rot2);
```



Creating a Transparency in the First Body

This series of commands illustrates how to create and attach a transparency to a body. The animation object stores the body geometry as patches. This example manipulates the transparency properties of these patches (see Patch Properties).

Note The use of transparencies might decrease animation speed on platforms that use software OpenGL® rendering (see `opengl`).

- 1 Change the body patch properties. Use the `Aero.Body PatchHandles` property to get the patch handles for the first body.

```
patchHandles2 = h.Bodies{1}.PatchHandles;
```

- 2 Set the face and edge alpha values that you want for the transparency.

```
desiredFaceTransparency = .3;  
desiredEdgeTransparency = 1;
```

- 3 Get the current face and edge alpha data and change all values to the alpha values that you want. In the figure, the first body now has a transparency.

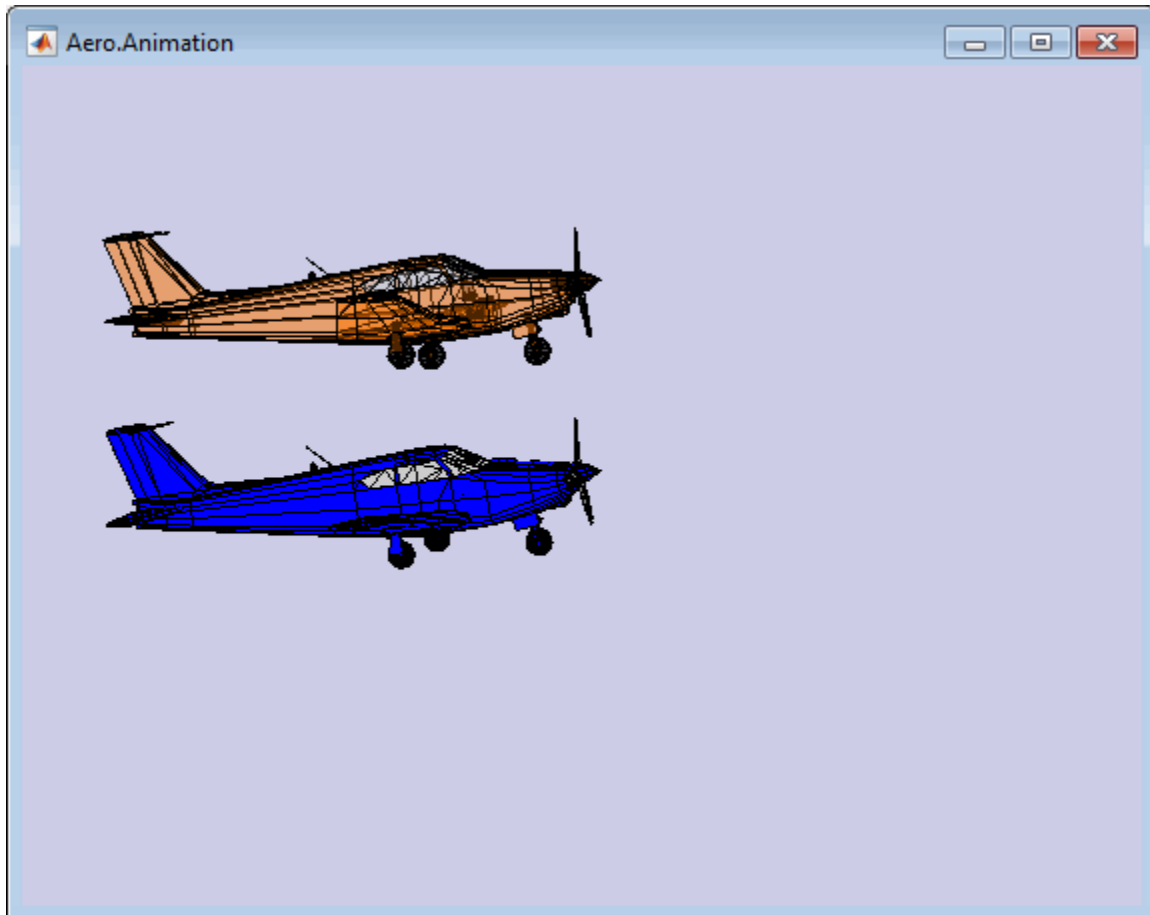
```
for k = 1:size(patchHandles2,1)  
    tempFaceAlpha = get(patchHandles2(k), 'FaceVertexAlphaData');
```



```

tempEdgeAlpha = get(patchHandles2(k), 'EdgeAlpha');
set(patchHandles2(k), ...
    'FaceVertexAlphaData', repmat(desiredFaceTransparency, size(tempFaceAlpha)));
set(patchHandles2(k), ...
    'EdgeAlpha', repmat(desiredEdgeTransparency, size(tempEdgeAlpha)));
end

```



Changing the Color of the Second Body

This series of commands illustrates how to change the color of a body. The animation object stores the body geometry as patches. This example manipulates the `FaceVertexColorData` property of these patches.

- 1 Change the body patch properties. Use the `Aero.Body PatchHandles` property to get the patch handles for the first body.

```
patchHandles3 = h.Bodies{2}.PatchHandles;
```

- 2 Set the patch color to red.

```
desiredColor = [1 0 0];
```

- 3 Get the current face color and data and propagate the new patch color, red, to the face.

- The `if` condition prevents the windows from being colored.
- The `name` property is stored in the body geometry data (`h.Bodies{2}.Geometry.FaceVertexColorData(k).name`).

- The code changes only the indices in `patchHandles3` with nonwindow counterparts in the body geometry data.

Note If you cannot access the `name` property to determine the parts of the vehicle to color, you must use an alternative way to selectively color your vehicle.

```
for k = 1:size(patchHandles3,1)
    tempFaceColor = get(patchHandles3(k),'FaceVertexCData');
    tempName = h.Bodies{2}.Geometry.FaceVertexColorData(k).name;
    if isempty(strfind(tempName,'Windshield')) &&...
        isempty(strfind(tempName,'front-windows')) &&...
        isempty(strfind(tempName,'rear-windows'))
        set(patchHandles3(k),...
            'FaceVertexCData', repmat(desiredColor,[size(tempFaceColor,1),1]));
    end
end
```

Turning Off the Landing Gear of the Second Body

This command series illustrates how to turn off the landing gear on the second body by turning off the visibility of all the vehicle parts associated with the landing gear.

Note The indices into the `patchHandles3` vector are determined from the `name` property. If you cannot access the `name` property to determine the indices, you must use an alternative way to determine the indices that correspond to the geometry parts.

```
for k = [1:8,11:14,52:57]
    set(patchHandles3(k),'Visible','off')
end
```

Aero.VirtualRealityAnimation Objects

The Aerospace Toolbox interface to virtual reality animation objects uses the Simulink 3D Animation software. For more information, see `Aero.VirtualRealityAnimation`, `Aero.Node`, and `Aero.Viewpoint`.

- Create, configure, and initialize an animation object.
- Enable the tracking of changes to virtual worlds.
- Load the animation world.
- Load time series data for simulation.
- Set coordination information for the object.
- Add a chase helicopter to the object.
- Load time series data for chase helicopter simulation.
- Set coordination information for the new object.
- Add a new viewpoint for the helicopter.
- Play the animation.
- Create a new viewpoint.
- Add a route.
- Add another helicopter.
- Remove bodies.
- Revert to the original world.

Running the Example

- 1 Start the MATLAB software.
- 2 Enter `astvranim` in the MATLAB Command Window.

While running, the example performs several steps by issuing a series of commands.

Example of Visualize Aircraft Takeoff and Chase Helicopter with the Virtual Reality Animation Object

Visualize Aircraft Takeoff via Virtual Reality Animation Object

This example shows how to visualize aircraft takeoff and chase helicopter with the virtual reality animation object. In this example, you can use the `Aero.VirtualRealityAnimation` object to set up a virtual reality animation based on the `asttkoff.wrl` file. The scene simulates an aircraft takeoff. The example adds a chase vehicle to the simulation and a chase viewpoint associated with the new vehicle.

Create the Animation Object

This code creates an instance of the `Aero.VirtualRealityAnimation` object.

```
h = Aero.VirtualRealityAnimation;
```

Set the Animation Object Properties

This code sets the number of frames per second and the seconds of animation data per second time scaling. 'FramesPerSecond' controls the rate at which frames are displayed in the figure window. 'TimeScaling' is the seconds of animation data per second time scaling.

The 'TimeScaling' and 'FramesPerSecond' properties determine the time step of the simulation. The settings in this example result in a time step of approximately 0.5s. The equation is:

$(1/\text{FramesPerSecond}) * \text{TimeScaling} + \text{extra terms to handle for sub-second precision.}$

```
h.FramesPerSecond = 10;  
h.TimeScaling = 5;
```

This code sets the `.wrl` file to be used in the virtual reality animation.

```
h.VRWorldFilename = [matlabroot, '/toolbox/aero/astdemos/asttkoff.wrl'];
```

Change Directory

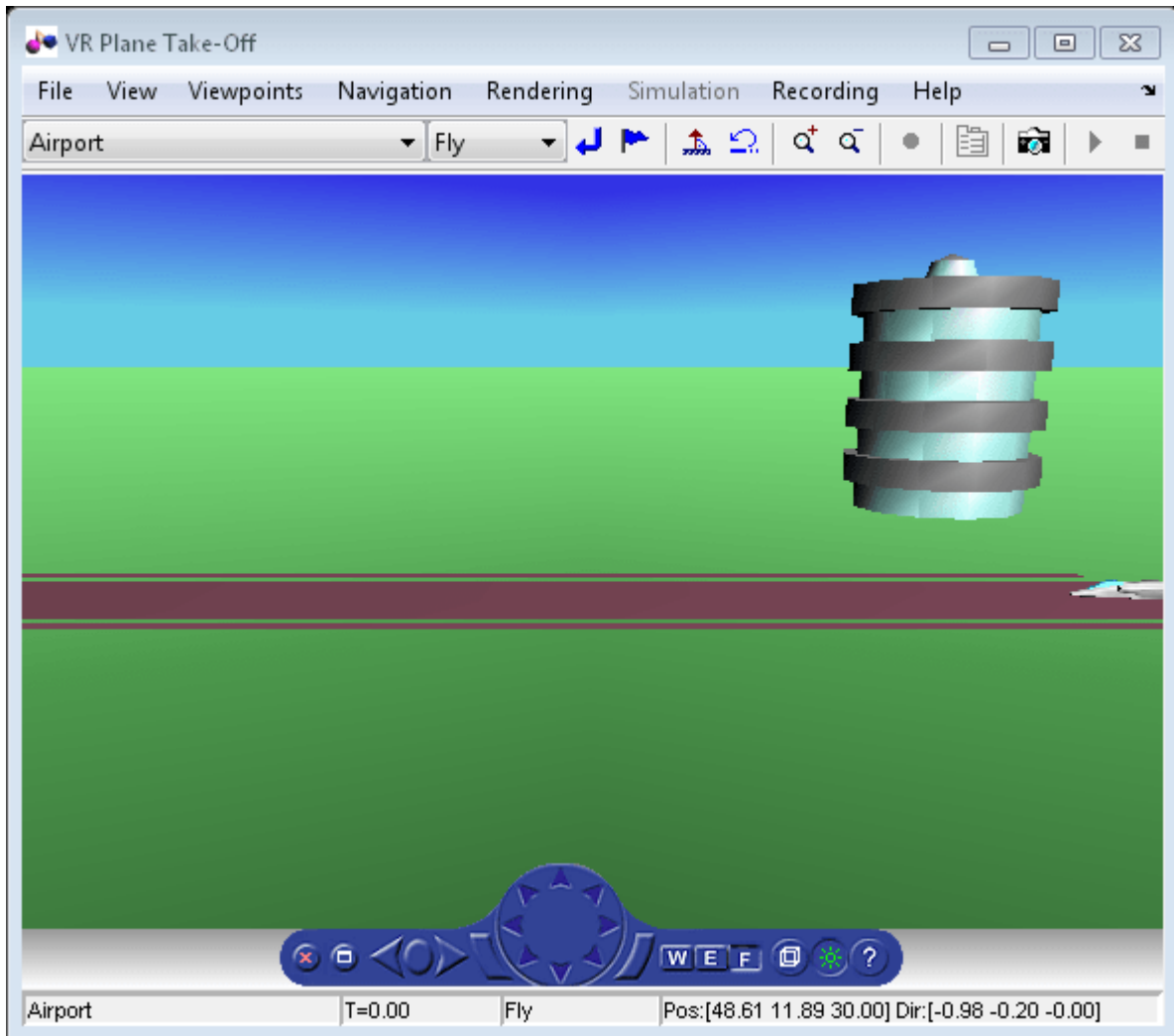
The `VirtualRealityAnimation` object methods use temporary `.wrl` files to keep track of changes to the world. This requires the directory containing the original `.wrl` file to be writable. This code runs the example from a temporary directory to ensure there are no issues with directory permissions. Note, a license for Simulink® 3D Animation™ is required to run this example.

```
% Copy file to temporary directory  
copyfile(h.VRWorldFilename, [tempdir, 'asttkoff.wrl'], 'f');  
% Set world filename to the copied .wrl file.  
h.VRWorldFilename = [tempdir, 'asttkoff.wrl'];
```

Initialize the Virtual Reality Animation Object

The `initialize` method loads the animation world described in the 'VRWorldFilename' field of the animation object. When parsing the world, node objects are created for existing nodes with DEF names. The `initialize` method also opens the Simulink 3D Animation viewer.

```
h.initialize();
```



Set Additional Node Information

This code sets simulation timeseries data. `takeoffData.mat` contains logged simulated data. `takeoffData` is set up as a 'StructureWithTime', which is one of the default data formats.

```
load takeoffData
[~, idxPlane] = find(strcmp('Plane', h.nodeInfo));
h.Nodes{idxPlane}.TimeseriesSource = takeoffData;
h.Nodes{idxPlane}.TimeseriesSourceType = 'StructureWithTime';
```

Set Coordinate Transform Function

The virtual reality animation object expects positions and rotations in aerospace body coordinates. If the input data is different, you must create a coordinate transformation function in order to correctly line up the position and rotation data with the surrounding objects in the virtual world. This code sets the coordinate transformation function for the virtual reality animation.

In this particular case, if the input translation coordinates are $[x1, y1, z1]$, they must be adjusted as follows: $[X, Y, Z] = -[y1, x1, z1]$. The custom transform function can be seen here: `matlabroot/toolbox/aero/astdemos/vr_animCustomTransform.m`

```
h.Nodes{idxPlane}.CoordTransformFcn = @vranimCustomTransform;
```

Add a Chase Helicopter

This code shows how to add a chase helicopter to the animation object.

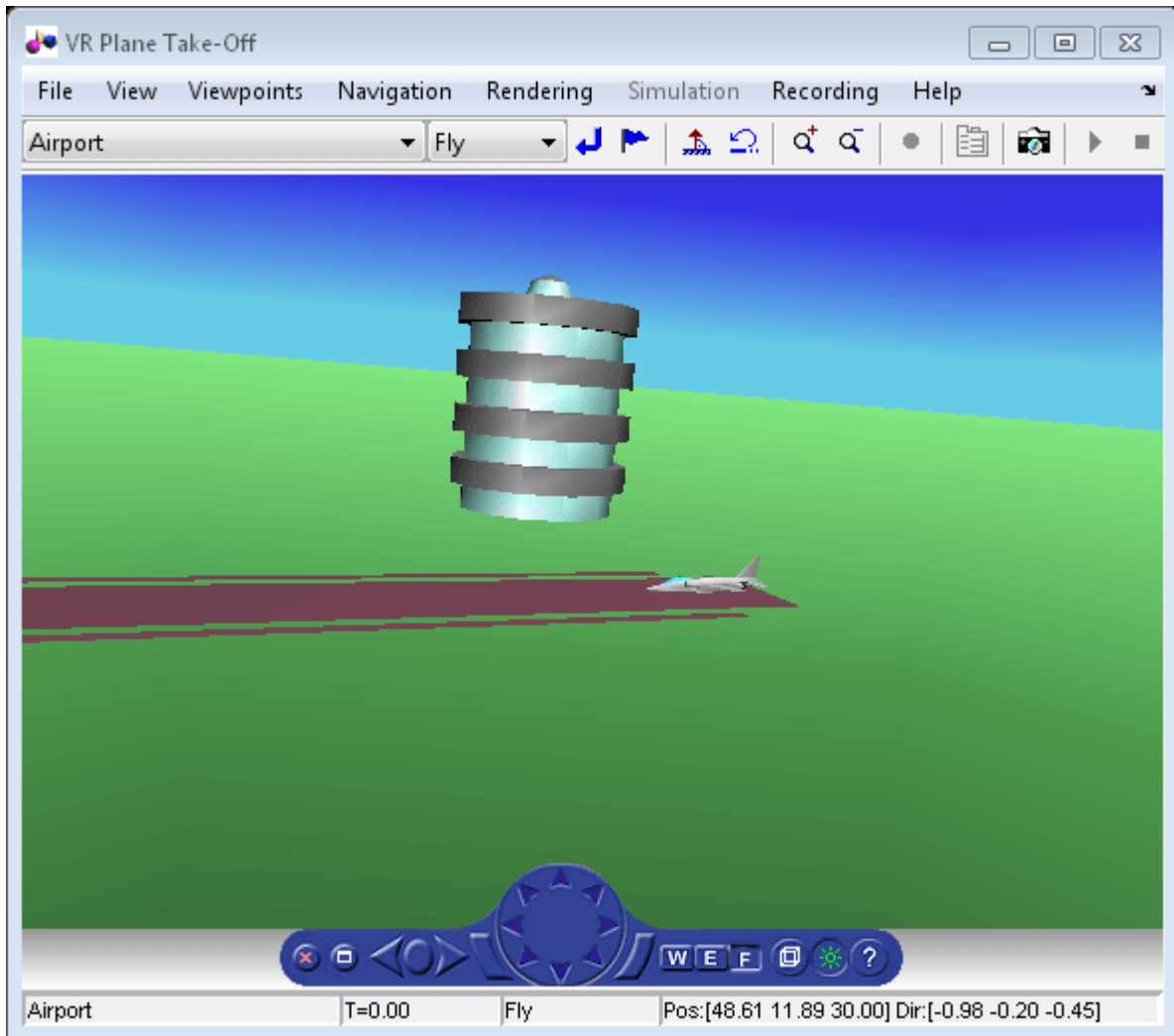
You can view all the nodes currently in the virtual reality animation object by using the `nodeInfo` method. When called with no output argument, this method prints the node information to the command window. With an output argument, the method sets node information to that argument.

```
h.nodeInfo;
```

```
Node Information
1   Camera1
2   Plane
3   _v2
4   Block
5   Terminal
6   _v3
7   Lighthouse
8   _v1
```

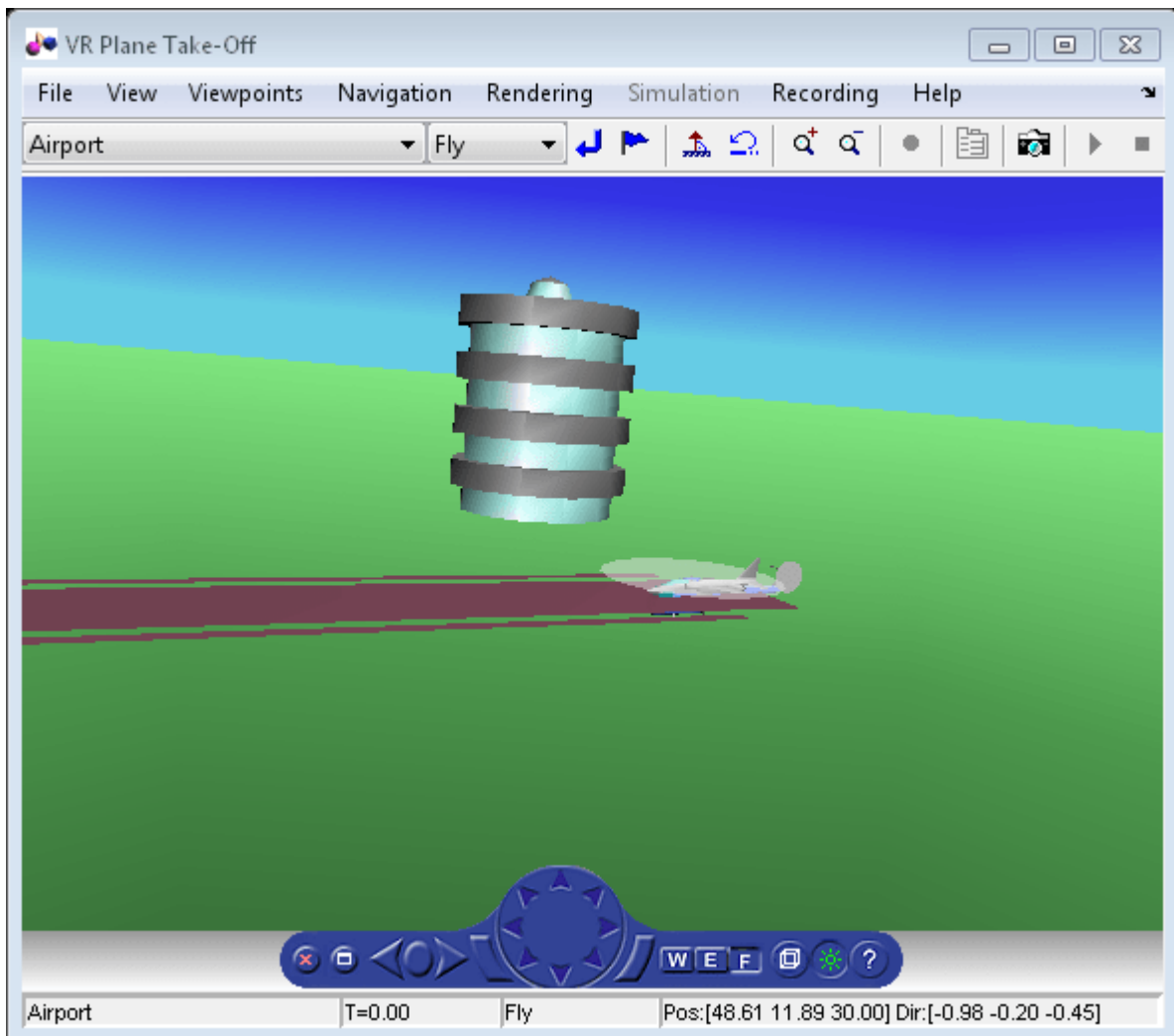
This code moves the camera angle of the virtual reality figure to view the aircraft.

```
set(h.VRFigure, 'CameraDirection', [0.45 0 -1]);
```



Use the `addNode` method to add another node to the object. By default, each time you add or remove a node or route, or when you call the `saveas` method, Aerospace Toolbox displays a message about the current `.wrl` file location. To disable this message, set the `ShowSaveWarning` property in the `VirtualRealityAnimation` object.

```
h.ShowSaveWarning = 0;  
h.addNode('Lynx',[matlabroot, '/toolbox/aero/astdemos/chaseHelicopter.wrl']);
```



Another call to `nodeInfo` shows the newly added Node objects.

`h.nodeInfo`

Node Information

```

1   Camera1
2   Plane
3   _V2
4   Block
5   Terminal
6   _v3
7   Lighthouse
8   _v1
9   Lynx
10  Lynx_Inline

```

Adjust newly added helicopter to sit on runway.

```

[~, idxLynx] = find(strcmp('Lynx',h.nodeInfo));
h.Nodes{idxLynx}.VRNode.translation = [0 1.5 0];

```

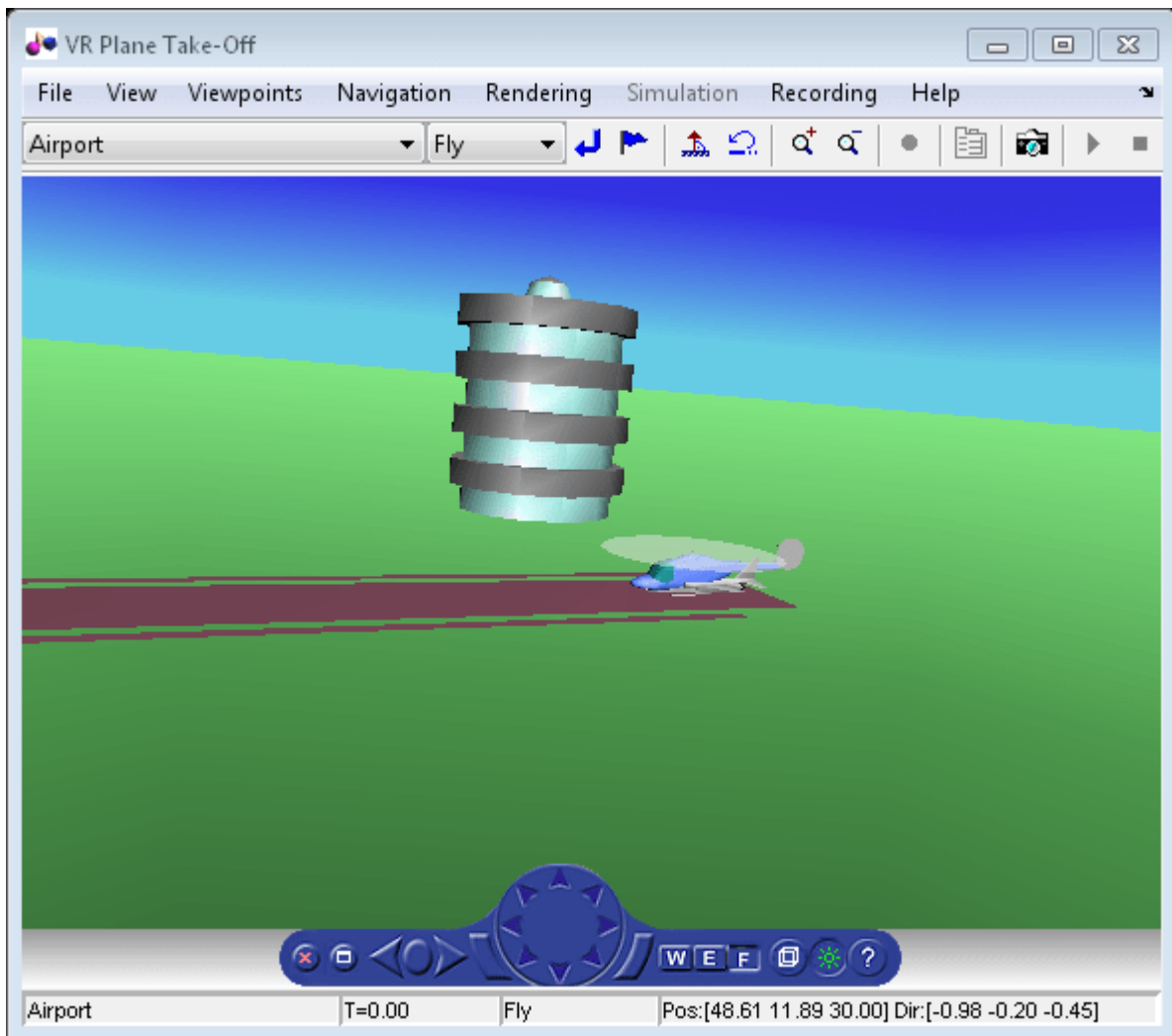

This code sets data properties for the chase helicopter. The 'TimeseriesSourceType' is the default 'Array6DoF', so no additional property changes are needed. The same coordinate transform function (vranimCustomTransform) is used for this node as the preceding node. The previous call to nodeInfo returned the node index (2).

```
load chaseData
h.Nodes{idxLynx}.TimeseriesSource = chaseData;
h.Nodes{idxLynx}.CoordTransformFcn = @vranimCustomTransform;
```

Create New Viewpoint

This code uses the addViewpoint method to create a new viewpoint named 'chaseView'. The new viewpoint will appear in the viewpoint pull-down menu in the virtual reality window as "View From Helicopter". Another call to nodeInfo shows the newly added node objects. The node is created as a child of the chase helicopter.

```
h.addViewpoint(h.Nodes{idxLynx}.VRNode, 'children', 'chaseView', 'View From Helicopter');
```



Play Animation

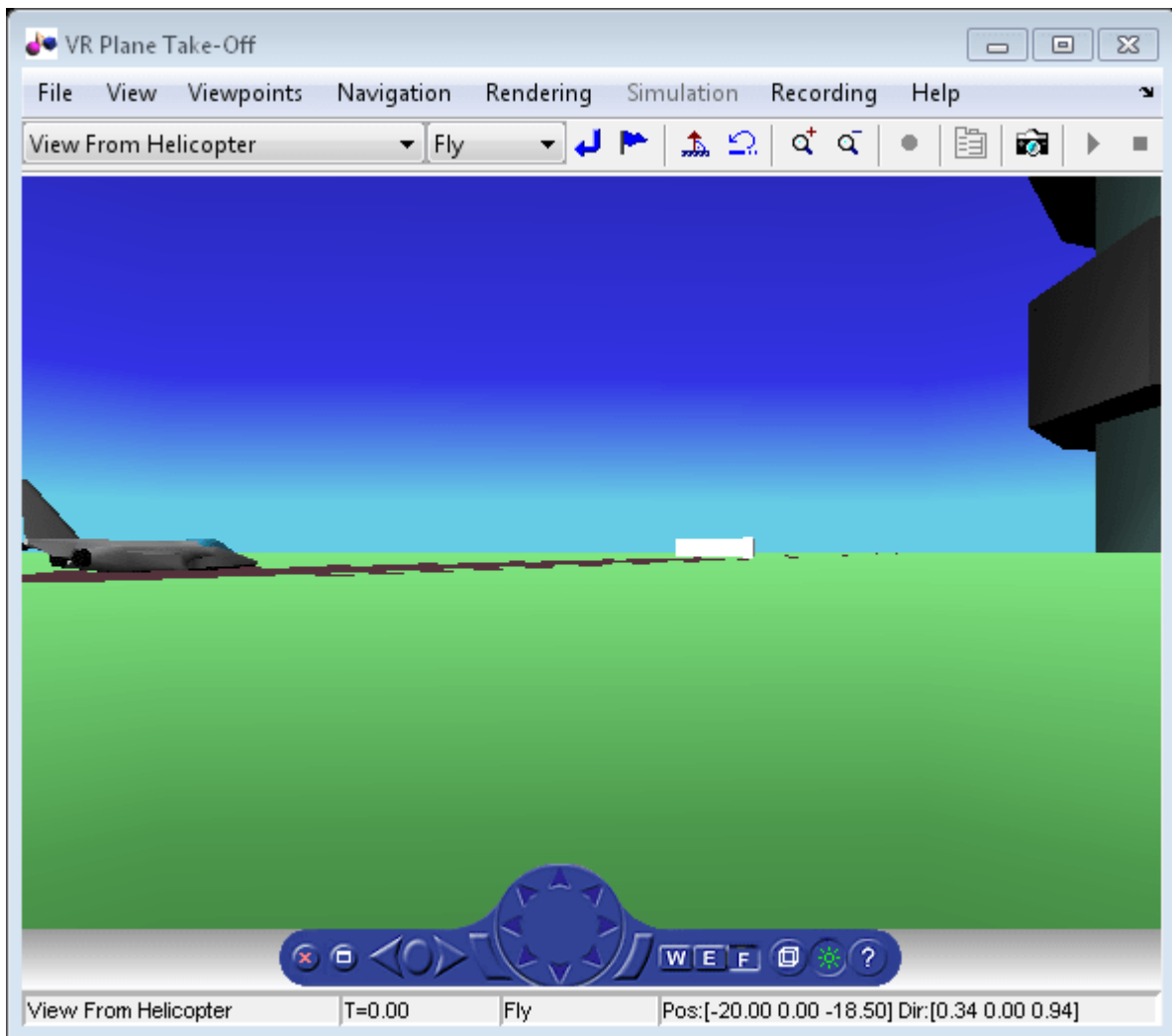
The play method runs the simulation for the specified timeseries data.

```
h.play();
```

Play Animation From Helicopter

This code sets the orientation of the viewpoint via the `vrnode` object associated with the node object for the viewpoint. In this case, it will change the viewpoint to look out the left side of the helicopter at the plane.

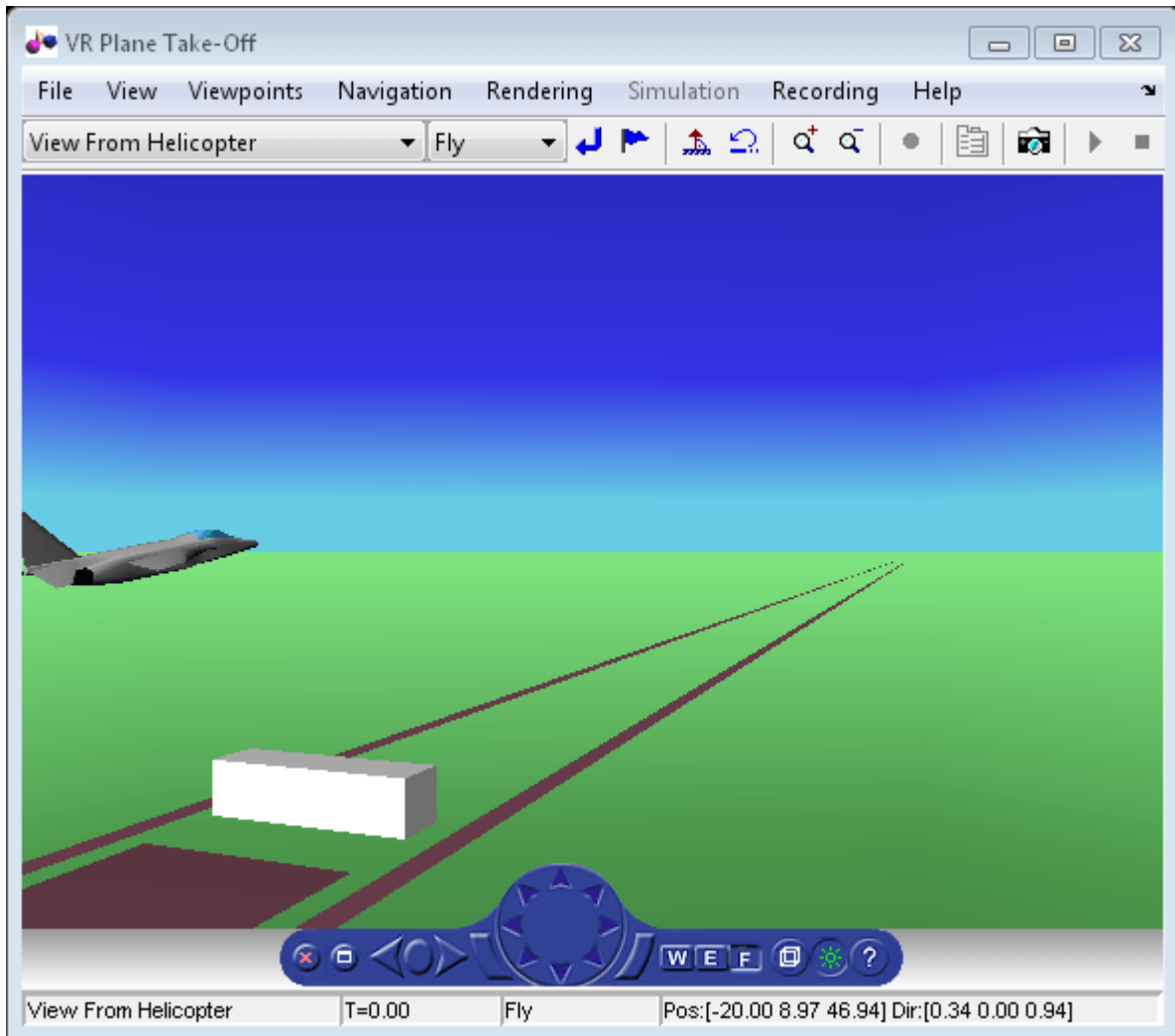
```
[~, idxChaseView] = find(strcmp('chaseView',h.nodeInfo));
h.Nodes{idxChaseView}.VRNode.orientation = [0 1 0 convang(200,'deg','rad')];
set(h.VRFigure,'Viewpoint','View From Helicopter');
```



Add ROUTE

This code calls the `addRoute` method to add a ROUTE command to connect the plane position to the Camera1 node. This will allow for the "Ride on the Plane" viewpoint to function as intended.

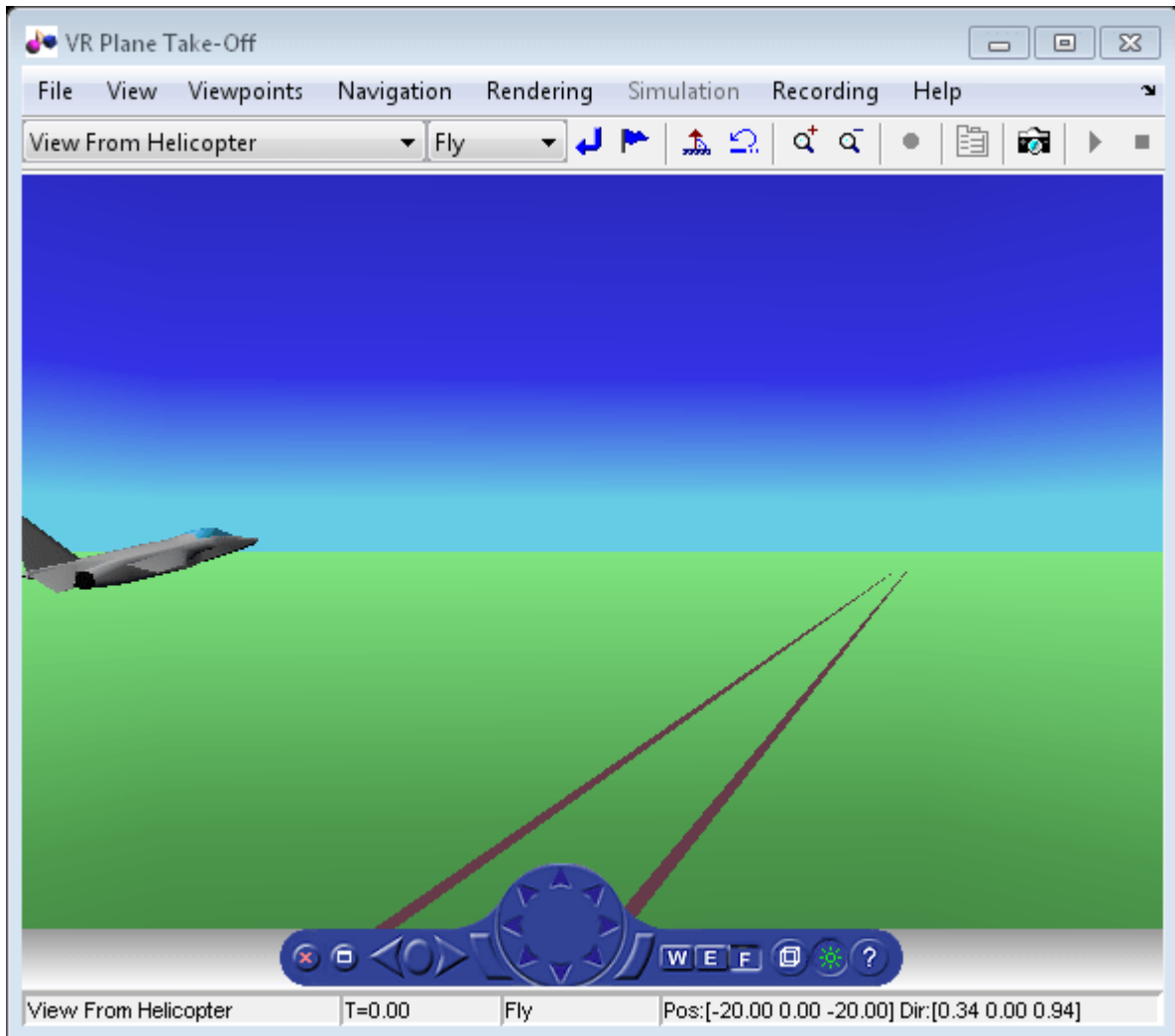
```
h.addRoute('Plane','translation','Camera1','translation');
```



The scene from the helicopter viewpoint

This code plays the animation.

```
h.play();
```



Add Another Body

This code adds another helicopter to the scene. It also changes to another viewpoint to view all three bodies in the scene at once.

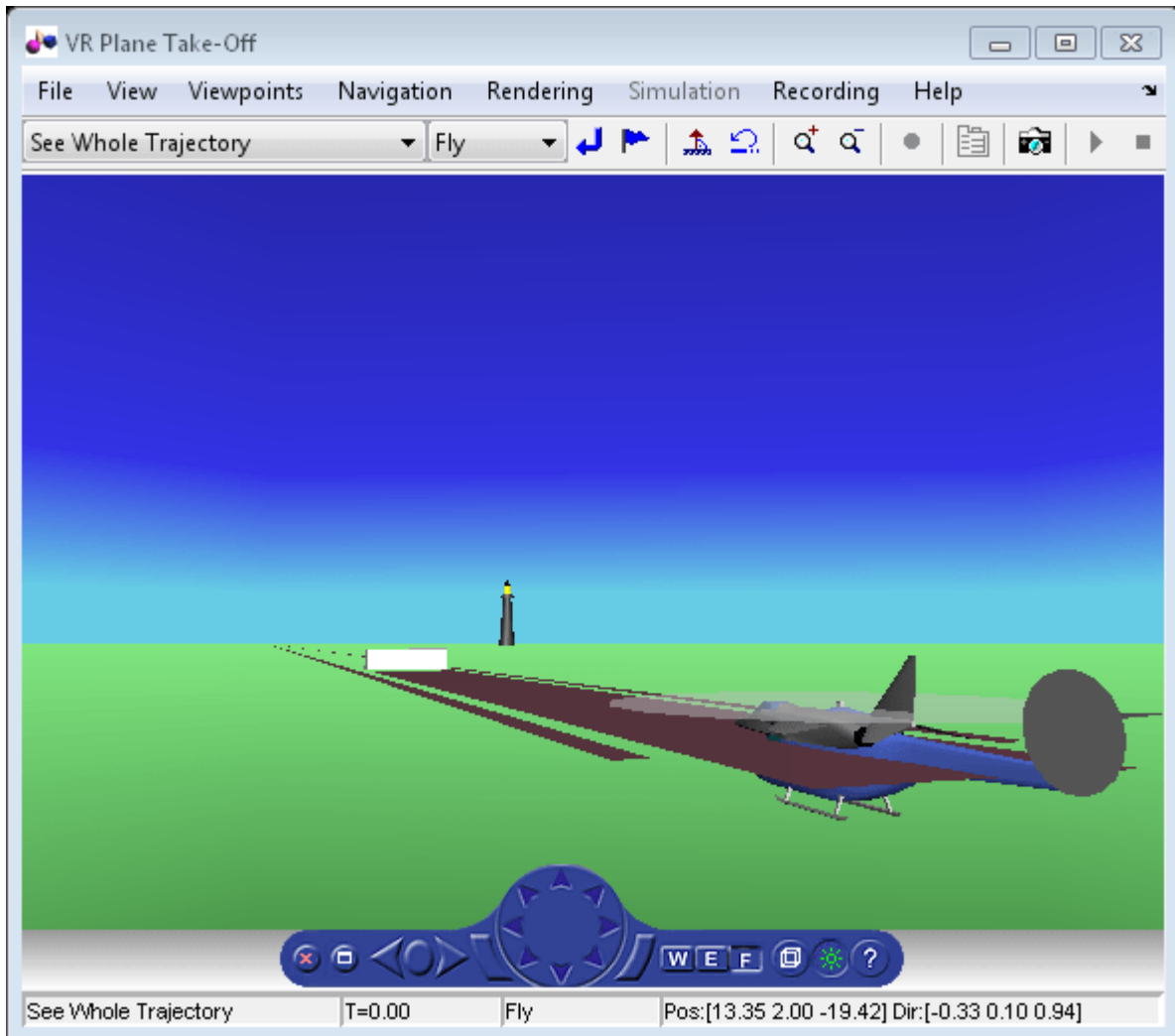
```
set(h.VRFigure, 'Viewpoint', 'See Whole Trajectory');
h.addNode('Lynx1', [matlabroot, '/toolbox/aero/astdemos/chaseHelicopter.wrl']);
h.nodeInfo
```

```
Node Information
1   Camera1
2   Plane
3   _v2
4   Block
5   Terminal
6   _v3
7   Lighthouse
8   _v1
9   Lynx
10  Lynx_Inline
```

```

11 chaseView
12 Lynx1
13 Lynx1_Inline

```



Adjust newly added helicopter to sit above runway.

```

[~, idxLynx1] = find(strcmp('Lynx1',h.nodeInfo));
h.Nodes{idxLynx1}.VRNode.translation = [0 1.3 0];

```

Remove Body

This code uses the `removeNode` method to remove the second helicopter. `removeNode` takes either the node name or node index (as obtained from `nodeInfo`). The associated inline node is removed as well.

```

h.removeNode('Lynx1');
h.nodeInfo

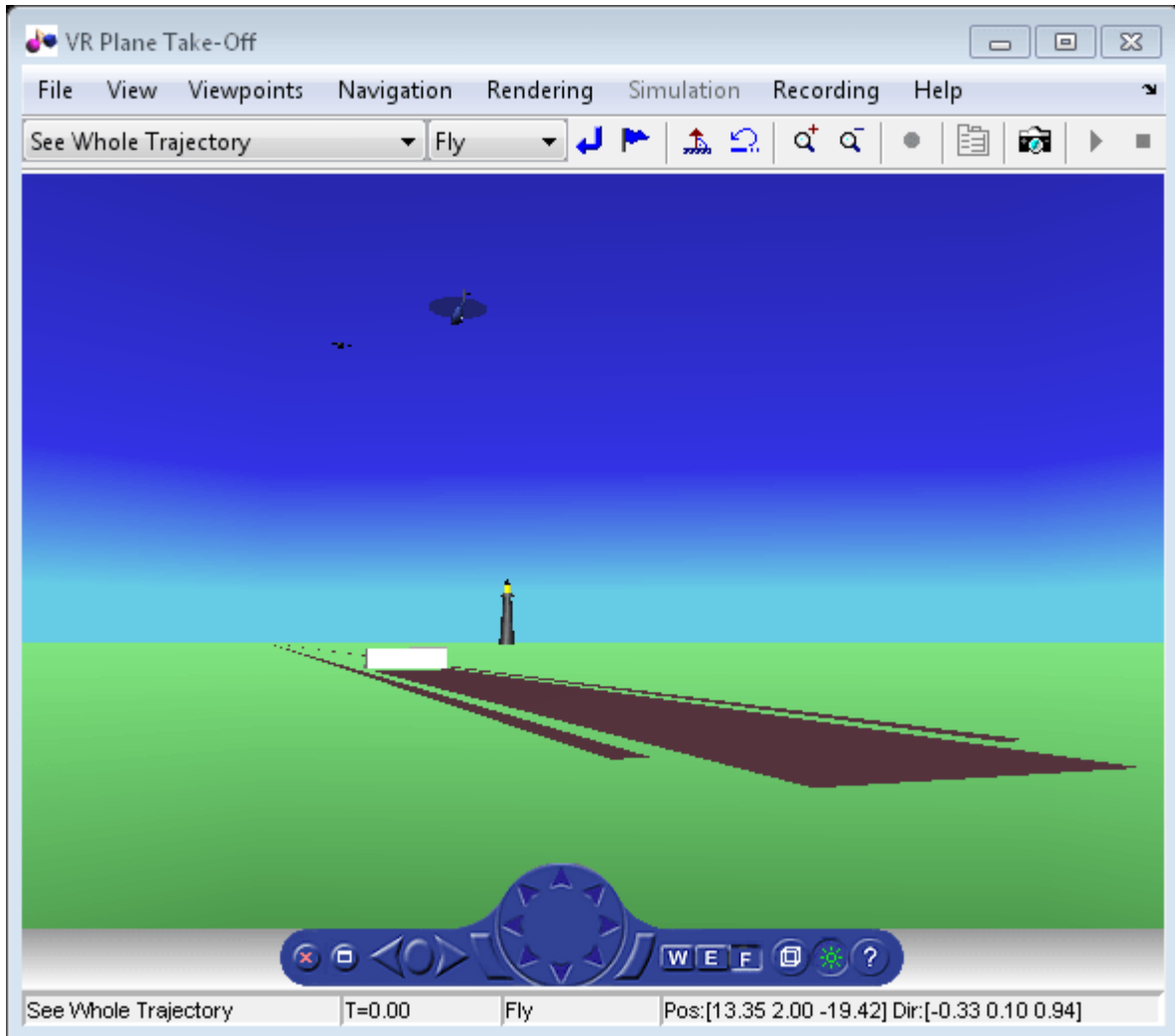
```

```

Node Information
1 Camera1

```

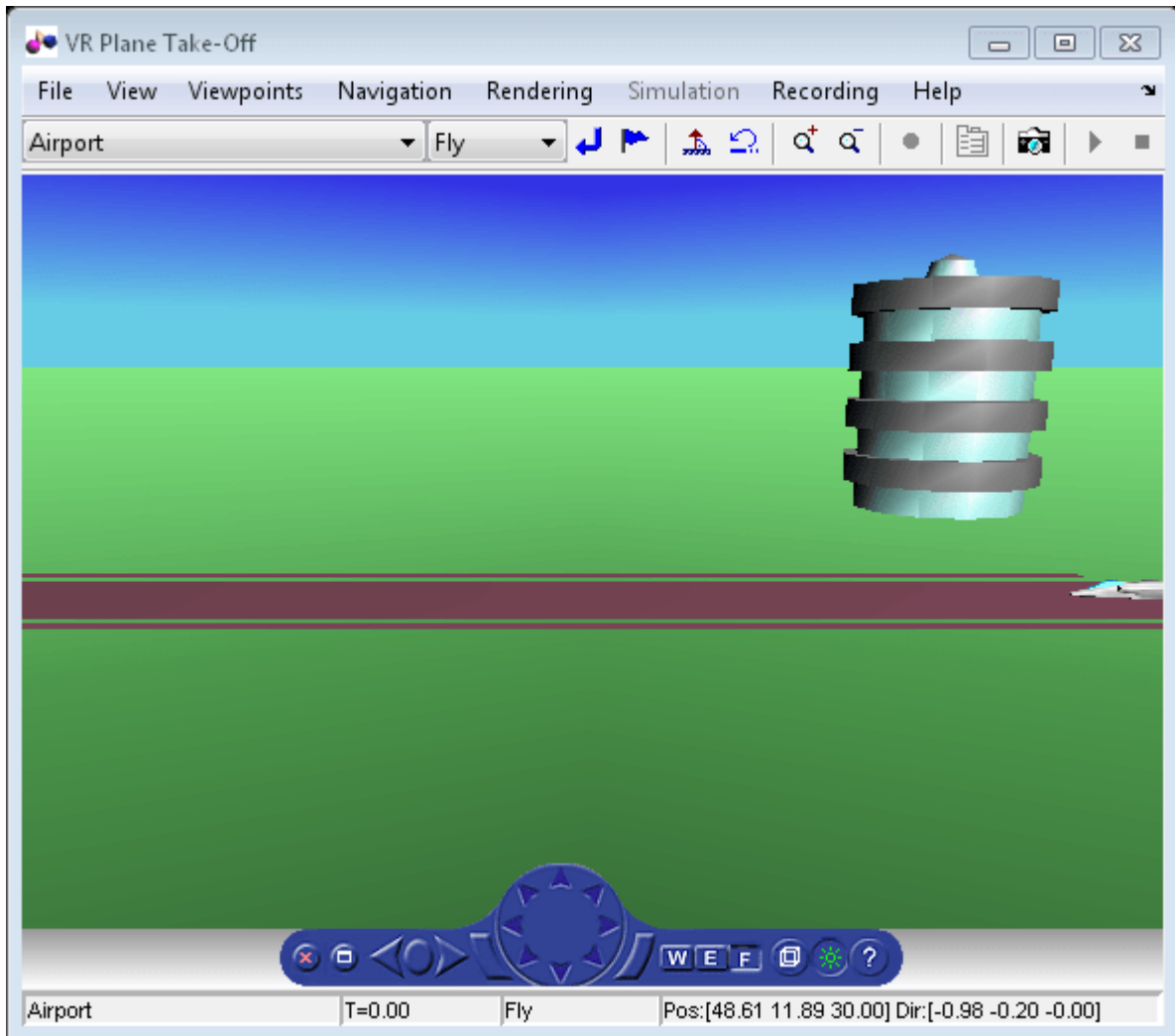
```
2 Plane
3 _V2
4 Block
5 Terminal
6 _v3
7 Lighthouse
8 _v1
9 Lynx
10 Lynx_Inline
11 chaseView
```



Revert To Original World

The original filename is stored in the 'VRWorldOldFilename' property of the animation object. To bring up the original world, set 'VRWorldFilename' to the original name and reinitializing it.

```
h.VRWorldFilename = h.VRWorldOldFilename{1};
h.initialize();
```



Close and Delete World

To close and delete

```
h.delete();
```

Aero.FlightGearAnimation Objects

The Aerospace Toolbox interface to the FlightGear flight simulator enables you to visualize flight data in a three-dimensional environment. The third-party FlightGear simulator is an open source software package available through a GNU® General Public License (GPL). This section describes how to obtain and install the third-party FlightGear flight simulator. It also describes how to play back 3-D flight data by using a FlightGear example, provided with your Aerospace Toolbox software.

About the FlightGear Interface

The FlightGear flight simulator interface included with the Aerospace Toolbox product is a unidirectional transmission link from the MATLAB software to FlightGear. It uses FlightGear's published `net_fdm` binary data exchange protocol. Data is transmitted via UDP network packets to a running instance of FlightGear. The toolbox supports multiple standard binary distributions of FlightGear. For interface details, see “Flight Simulator Interface Example” on page 2-42.

FlightGear is a separate software entity that is not created, owned, or maintained by MathWorks.

- To report bugs in or request enhancements to the Aerospace Toolbox FlightGear interface, contact MathWorks technical support at <https://www.mathworks.com/support/>.
- To report bugs or request enhancements to FlightGear itself, go to www.flightgear.org and use the contact page.

Supported FlightGear Versions

The Aerospace Toolbox product supports FlightGear versions starting from v2.6.

Obtaining FlightGear Software

You can obtain FlightGear software from www.flightgear.org in the download area or by ordering CDs from FlightGear. The download area contains extensive documentation for installation and configuration. Because FlightGear is an open source project, source downloads are also available for customization and porting to custom environments.

Configuring Your Computer for FlightGear

You must have a high-performance graphics card with stable drivers to use FlightGear. For more information, see the FlightGear CD distribution or the hardware requirements and documentation areas of the FlightGear website, www.flightgear.org.

Setup on Linux, Mac OS X, and Other Platforms

FlightGear distributions are available for Linux®, Mac OS X, and other UNIX® platforms from the FlightGear website, www.flightgear.org. Installation on these platforms, like Windows®, requires careful configuration of graphics cards and drivers. Consult the documentation and hardware requirements sections at the FlightGear website.

FlightGear and Video Cards in Windows Systems

Your computer built-in video card, such as NVIDIA® cards, can have issues working with FlightGear shaders. Consider this workaround:

- Disable the FlightGear shaders by specifying the `DisableShaders` property of the `Aero.FlightGearAnimation` object to the `GenerateRunScript` (`Aero.FlightGearAnimation`) method.

Install and Start FlightGear

The extensive FlightGear documentation guides you through the installation. For complete installation instructions, consult the documentation section of the FlightGear website www.flightgear.org.

Note:

- Generous central processor speed, system and video RAM, and virtual memory are essential for good flight simulator performance.

For more information, see http://wiki.flightgear.org/Hardware_recommendations.
- Have sufficient disk space for the FlightGear download and installation.
- Before you install FlightGear, configure your computer graphics card. See the preceding section, “Configuring Your Computer for FlightGear” on page 2-40.
- Before installing FlightGear, shut down all running applications (including the MATLAB software).
- Install FlightGear in a folder path name composed of ASCII characters.
- The operational stability of FlightGear is especially sensitive during startup. It is best to not move, resize, mouse over, overlap, or cover up the FlightGear window until the initial simulation scene appears after the startup splash screen fades out.
- The current releases of FlightGear are optimized for flight visualization at altitudes below 100,000 feet. FlightGear does not work well or at all with very high altitude and orbital views.

The Aerospace Toolbox product supports FlightGear on a number of platforms (System Requirements). The following table lists the properties to be aware of before you start using FlightGear.

FlightGear Property	Folder Description	Platforms	Typical Location
FlightGearBase-Directory	FlightGear installation folder.	Windows	C:\Program Files\FlightGear (default)
		Linux	Directory into which you installed FlightGear
		Mac	/Applications (folder into which you dragged the FlightGear icon)
GeometryModelName	Model geometry folder	Windows	C:\Program Files\FlightGear\data\Aircraft\HL20 (default)
		Linux	\$FlightGearBaseDirectory/data/Aircraft/HL20
		Mac	\$FlightGearBaseDirectory/-FlightGear.app/Contents/Resources/data/Aircraft/HL20

Installing Additional FlightGear Scenery

When you install the FlightGear software, the installation provides a basic level of scenery files. The FlightGear documentation guides you through installing scenery as part the general FlightGear installation.

If you need to install more FlightGear scenery files, see the instructions at <http://www.flightgear.org>. Those instructions describe how to install the additional scenery in a default location.

If you install additional scenery in a non-standard location, you may need to update the `FG_SCENERY` environment variable in the script output from the `GenerateRunScript` function to include the new path. For a description of the `FG_SCENERY` variable, see the documentation at <http://www.flightgear.org>.

If you do not download scenery in advance, you can direct FlightGear to download it automatically during simulation using the `InstallScenery` property of the `Aero.FlightGearAnimation` object for the `GenerateRunScript` (`Aero.FlightGearAnimation`) method.

For Windows systems, you may encounter an error message while launching FlightGear with the `InstallScenery` option enabled:

```
Error creating directory: No such file or directory
```

This error likely indicates that your default FlightGear download folder is not writeable, the path cannot be resolved, or the path contains UNC path names. To work around the issue, edit the `runfg.bat` file to specify a new folder path to store the scenery data:

- 1 Edit `runfg.bat`.
- 2 To the list of command options, append `--download-dir=` and specify a folder to which to download the scenery data. For example:

```
--download-dir=C:\Users\user1\Documents\FlightGear
```

All data downloaded during this FlightGear session is saved to the specified directory. To avoid downloading duplicate scenery data, use the same directory in succeeding FlightGear sessions

- 3 To open FlightGear, run `runfg.bat`.

Note Each time that you run the `GenerateRunScript` function, it creates a new script. It overwrites any edits that you have added.

Flight Simulator Interface Example

The Aerospace Toolbox product provides an example named `Displaying Flight Trajectory Data`. This example shows you how you can visualize flight trajectories with `FlightGear Animation` object. The example is intended to be modified depending on the particulars of your FlightGear installation. Use this example to play back your own 3-D flight data with FlightGear.

Before attempting to simulate this model, you must have FlightGear installed and configured. See “About the FlightGear Interface” on page 2-40.

To run the example:

- Import the aircraft geometry into FlightGear.
- Run the example. The example performs the following steps:
 - Loads recorded trajectory data.
 - Creates a time series object from trajectory data.
 - Creates a FlightGearAnimation object.
- Modify the animation object properties, if needed.
- Create a run script for launching the FlightGear flight simulator.
- Start the FlightGear flight simulator.
- Play back the flight trajectory.

Import the Aircraft Geometry into FlightGear

Before running the example, copy the aircraft geometry model into FlightGear. From the following procedures, choose the one appropriate for your platform. This section assumes that you have read “Install and Start FlightGear” on page 2-41.

If your platform is Windows:

- 1 Go to your installed FlightGear folder. Open the data folder, and then the Aircraft folder:
FlightGear\data\Aircraft.
- 2 If you have previously run the Aerospace Blockset NASA HL-20 with FlightGear Interface example, you might already have an HL20 subfolder there.

Otherwise, copy the HL20 folder from the *matlabroot\toolbox\ aero\astdemos* folder to the *FlightGear\data\Aircraft* folder. This folder contains the preconfigured geometries for the HL-20 simulation and *HL20-set.xml*. The file *matlabroot\toolbox\ aero\ aerodemos\HL20\models\HL20.xml* defines the geometry.

If your platform is Linux:

- 1 Go to your installed FlightGear folder. Open the data folder, then the Aircraft folder:
\$FlightGearBaseDirectory/data/Aircraft/.
- 2 If you have previously run the Aerospace Blockset NASA HL-20 with FlightGear Interface example, you might already have an HL20 subfolder there. If that is the case, you do not have to do anything, because you can use the existing geometry model.

Otherwise, copy the HL20 folder from the *matlabroot/toolbox/aero/aerodemos/* folder to the *\$FlightGearBaseDirectory/data/Aircraft/* folder. This folder contains the preconfigured geometries for the HL-20 simulation and *HL20-set.xml*. The file *matlabroot/toolbox/aero/aerodemos/HL20/models/HL20.xml* defines the geometry.

If your platform is Mac:

- 1 Open a terminal.
- 2 List the contents of the Aircraft folder. For example, type:

```
ls $FlightGearBaseDirectory/data/Aircraft/
```
- 3 If you have previously run the Aerospace Blockset NASA HL-20 with FlightGear Interface example, you might already have an HL20 subfolder there. In this case, you do not have to do anything, because you can use the existing geometry model. Continue to “Running the Example” on page 2-19.

Otherwise, copy the HL20 folder from the

`matlabroot/toolbox/aero/aerodemos/`

folder to the

`$FlightGearBaseDirectory/FlightGear.app/Contents/Resources/data/Aircraft/`

folder. This folder contains the preconfigured geometries for the HL-20 simulation and `HL20-set.xml`. The file `matlabroot/toolbox/aero/aerodemos/HL20/models/HL20.xml` defines the geometry.

Running the Example

- 1 Start the MATLAB software.
- 2 Enter `astfganim` in the MATLAB Command Window.

While running, the example performs several steps by issuing a series of commands.

Flight Trajectory Data

Loading Recorded Flight Trajectory Data

The flight trajectory data for this example is stored in a comma separated value formatted file. Using `dlmread`, the data is read from the file starting at row 1 and column 0, which omits the header information.

```
tdata = dlmread('asthl20log.csv', ',', 1, 0);
```

Creating a Time Series Object from Trajectory Data

The time series object, `ts`, is created from the latitude, longitude, altitude, Euler angle data, and the time array in `tdata` using the MATLAB `timeseries` command. Latitude, longitude, and Euler angles are also converted from degrees to radians using the `convang` function.

```
ts = timeseries([convang(tdata(:,[3 2]),'deg','rad') ...
               tdata(:,4) convang(tdata(:,5:7),'deg','rad')],tdata(:,1));
```

Creating a FlightGearAnimation Object

This series of commands creates a `FlightGearAnimation` object:

- 1 Open a `FlightGearAnimation` object.

```
h = fganimation;
```

- 2 Set `FlightGearAnimation` object properties for the time series.

```
h.TimeseriesSourceType = 'Timeseries';
h.TimeseriesSource = ts;
```

- 3 Set `FlightGearAnimation` object properties relating to `FlightGear`. These properties include the path to the installation folder, the version number, the aircraft geometry model, and the network information for the `FlightGear` flight simulator.

```
h.FlightGearBaseDirectory = 'C:\Program Files\FlightGear<your_FlightGear_version>';
h.GeometryModelName = 'HL20';
h.DestinationIpAddress = '127.0.0.1';
h.DestinationPort = '5502';
```

- 4 Set the initial conditions (location and orientation) for the `FlightGear` flight simulator.

```
h.AirportId = 'KSF0';
h.RunwayId = '10L';
h.InitialAltitude = 7224;
h.InitialHeading = 113;
h.OffsetDistance = 4.72;
h.OffsetAzimuth = 0;
```

- 5 Set the seconds of animation data per second of wall-clock time.

```
h.TimeScaling = 5;
```

- 6 Check the `FlightGearAnimation` object properties and their values.

```
get(h)
```

The example stops running and returns the `FlightGearAnimation` object, `h`:

```
TimeseriesSource: [1x1 timeseries]
TimeseriesSourceType: 'Timeseries'
TimeseriesReadFcn: @TimeseriesRead
    TimeScaling: 5
    FramesPerSecond: 12
FlightGearVersion: '2018.1'
    OutputFileName: 'runfg.bat'
FlightGearBaseDirectory: 'C:\Program Files\FlightGear<your_FlightGear_version>'
    GeometryModelName: 'HL20'
DestinationIpAddress: '127.0.0.1'
    DestinationPort: '5502'
        AirportId: 'KSF0'
        RunwayId: '10L'
InitialAltitude: 7224
InitialHeading: 113
OffsetDistance: 4.7200
    OffsetAzimuth: 0
        TStart: NaN
        TFinal: NaN
Architecture: 'Default'
```

You can now set the object properties for data playback (see “Modifying the FlightGearAnimation Object Properties” on page 2-46).

Modifying the FlightGearAnimation Object Properties

Modify the FlightGearAnimation object properties as needed. If your FlightGear installation folder is other than the one in the example (for example, FlightGear), modify the FlightGearBaseDirectory property by issuing the following command:

```
h.FlightGearBaseDirectory = 'C:\Program Files\FlightGear';
```

Similarly, if you want to use a particular file name for the run script, modify the OutputFileName property.

Verify the FlightGearAnimation object properties:

```
get(h)
```

You can now generate the run script (see “Generating the Run Script” on page 2-46).

Generating the Run Script

To start FlightGear with the initial conditions (location, date, time, weather, operating modes) that you want, create a run script by using the GenerateRunScript command:

```
GenerateRunScript(h)
```

By default, GenerateRunScript saves the run script as a text file named runfg.bat. You can specify a different name by modifying the OutputFileName property of the FlightGearAnimation object, as described in the previous step.

You do not need to generate the file each time the data is viewed, only when the initial conditions or FlightGear information changes.

You are now ready to start FlightGear (see “Starting the FlightGear Flight Simulator” on page 2-47).

Note The `FlightGearBaseDirectory` and `OutputFileName` properties must be composed of ASCII characters.

Starting the FlightGear Flight Simulator

To start FlightGear from the MATLAB command prompt, use the `system` command to execute the run script. Provide the name of the output file created by `GenerateRunScript` as the argument:

```
system('runfg.bat &');
```

FlightGear starts in a separate window.

Tip With the FlightGear window in focus, press the **V** key to alternate between the different aircraft views: cockpit, helicopter, chase, and so on.

You are now ready to play back data (see “Playing Back the Flight Trajectory” on page 2-47). If you cannot view scenes, see “Installing Additional FlightGear Scenery” on page 2-42.

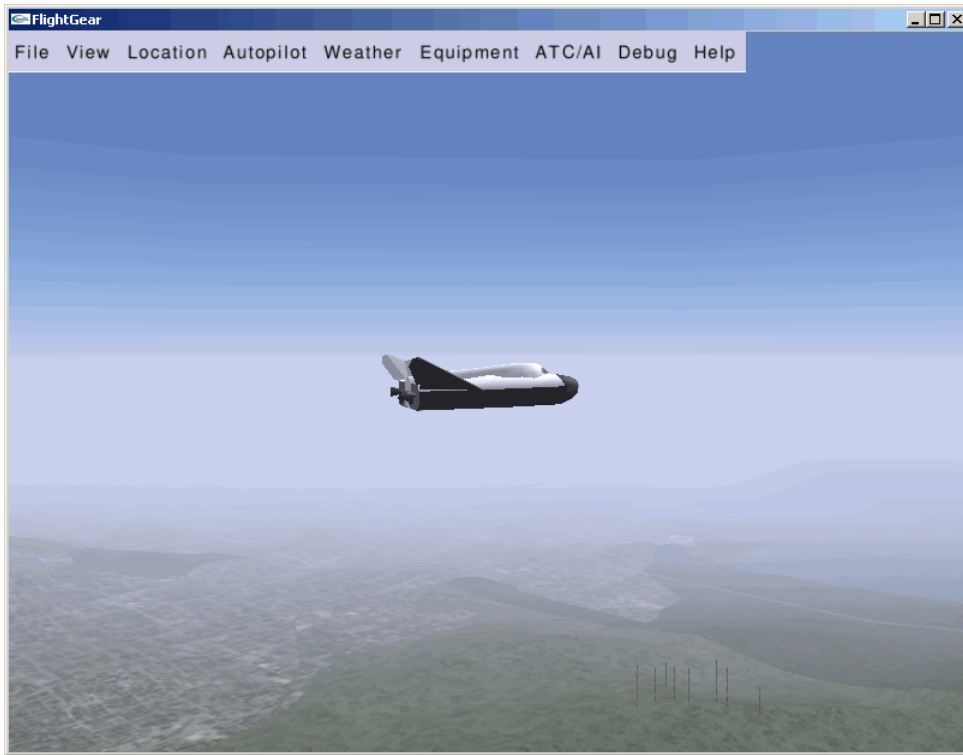
Tip If FlightGear uses more computer resources than you want, you can change its scheduling priority to a lesser one. For example, see commands like Windows `start` and Linux `nice` or their equivalents.

Playing Back the Flight Trajectory

Once FlightGear is running, the `FlightGearAnimation` object can start to communicate with FlightGear. To animate the flight trajectory data, use the `play` command:

```
play(h)
```

The following illustration shows a snapshot of flight data playback in tower view without yaw.



Create and Configure Flight Instrument Component and an Animation Object

You can display flight data using any of the standard flight instrument components:

- Airspeed indicator
- Altimeter
- Climb indicator
- Exhaust gas temperature (EGT) indicator
- Heading indicator
- Artificial horizon
- Revolutions per minute (RPM) indicator
- Turn coordinator

As a general workflow:

- 1 Load simulation data.
- 2 Create an animation object.
- 3 Create a figure window.
- 4 Create a flight control panel to contain the flight instrument components.
- 5 Create the flight instrument components.
- 6 Trigger a display of the animation in the instrument panel.

Note Use Aerospace Toolbox flight instruments only with figures created using the `uifigure` function. Apps created using GUIDE or the `figure` function do not support flight instrument components.

Load and Visualize Data

To load and visualize data, consider this workflow:

- 1 Load simulation data. For example, the `simdata` variable contains logged simulated flight trajectory data.


```
load simdata
```
- 2 To visualize animation data, create an animation object. For example:
 - a Create an `Aero.Animation` object.


```
h = Aero.Animation;
```
 - b Create a body using the `pa24-250_orange.ac` AC3D file and its associated patches.


```
h.createBody('pa24-250_orange.ac', 'Ac3d');
```
 - c Set up the bodies of the animation object `h`. Set the `TimeSeriesSource` property to the loaded `simdata`.


```
h.Bodies{1}.TimeSeriesSource = simdata;
```

- d Set up the camera and figure positions.

```
h.Camera.PositionFcn = @staticCameraPosition;
h.Figure.Position(1) = h.Figure.Position(1) + 572/2;
```

- e Create and show the figure graphics object for h.

```
h.updateBodies(simdata(1,1));
h.updateCamera(simdata(1,1));
h.show();
```

To create the flight instrument components, see “Create Flight Instrument Components” on page 2-50

Create Flight Instrument Components

This workflow assumes that you have loaded data and created an animation object as described in “Load and Visualize Data” on page 2-49.

- 1 Create a `uifigure` figure window. This example creates `fig`, to contain the flight instrument for `h`.

```
fig = uifigure('Name','Flight Instruments',...
'Position',[h.Figure.Position(1)-572 h.Figure.Position(2)+h.Figure.Position(4)-502 572 502],...
'Color',[0.2667 0.2706 0.2784],'Resize','off');
```

- 2 Create a flight instrument panel image for the flight instruments and save it as a graphic file, such as a PNG file.

- 3 Read the flight instrument panel image into MATLAB and create and load it into UI axes in App Designer using the `uiaxes` function. To display the flight instrument panel image in the current axes, use the `image` function. For example:

```
imgPanel = imread('astFlightInstrumentPanel.png');
ax = uiaxes('Parent',fig,'Visible','off','Position',[10 30 530 460],...
'BackgroundColor',[0.2667 0.2706 0.2784]);
image(ax,imgPanel);
```

- 4 Create a flight instruments component. For example, create an artificial horizon component. Specify the parent object as the `uifigure` and the position and size of the artificial horizon.

```
hor = uiaerohorizon('Parent',fig,'Position',[212 299 144 144]);
```

- 5 To trigger a display of the animation in the instrument panel, you must input a time step. For example, connect a time input device such as a slider or knob that can change the time. As you change the time on the time input device, the flight instrument component updates to show the result. This example uses the `uislider` function to create a slider component.

```
sl = uislider('Parent',fig,'Limits',[simdata(1,1),...
simdata(end,1)],'FontColor','white');
sl.Position = [50 60 450 3];
```

- 6 The slider component has a `ValueChangedFcn` callback, which executes when you move the slider thumb. To update the flight instruments and animation figure, assign the `ValueChangedFcn` callback to a helper function. This example uses the `astHelperFlightInstrumentsAnimation` helper function.

```
sl.ValueChangingFcn = @(sl,event)
astHelperFlightInstrumentsAnimation(sl,fig,simdata,h);
```

- 7 To display the time selected in the slider, use the `uicontrol` function to create a label component. This code creates the label text in white and places the label at position [230 10 90 30].

```
lbl = uicontrol('Parent',fig,'Text',['Time: ' num2str(sl.Value,4) ' sec'],'FontColor','white');
lbl.Position = [230 10 90 30];
```

For a complete example, see “Display Flight Trajectory Data Using Flight Instruments and Flight Animation” on page 5-111.

See Also

Functions

[imread](#) | [uiaeroairspeed](#) | [uiaeroaltimeter](#) | [uiaeroclimb](#) | [uiaeroegt](#) | [uiaeroheading](#) | [uiaerohorizon](#) | [uiaerorpm](#) | [uiaereturn](#) | [uiaxes](#) | [uifigure](#) | [uilabel](#) | [uislider](#)

Properties

[AirspeedIndicator Properties](#) | [Altimeter Properties](#) | [ArtificialHorizon Properties](#) | [ClimbIndicator Properties](#) | [EGTIndicator Properties](#) | [HeadingIndicator Properties](#) | [RPMIndicator Properties](#) | [TurnCoordinator Properties](#)

More About

- “Flight Instruments”
- “Display Flight Trajectory Data Using Flight Instruments and Flight Animation” on page 5-111
- “Flight Instrument Components in App Designer” on page 2-52

Flight Instrument Components in App Designer

Create aerospace-specific applications in App Designer using common aircraft flight instruments. App Designer is a rich development environment that provides layout and code views, a fully integrated version of the MATLAB editor, and a large set of interactive components. For more information on App Designer, see “Develop Apps Using App Designer”. To use the flight instrument components in App Designer, you must have an Aerospace Toolbox license.

For a simple flight instruments app example that uses the App Designer, see the Getting Started examples when you first start App Designer. To create an app to visualize saved flight data for a Piper PA-24 Comanche, use this workflow.

- 1 Start App Designer by typing `appdesigner` at the command line, and then select **Blank App** on the Getting Started page.
- 2 Drag aerospace components from the **Component Library** to the app canvas.
- 3 To load simulation data, add a `startup` function to the app, and then create an animation object.
- 4 Enter the callbacks, functions, and properties for the components to the app. Also add associated code.
- 5 Trigger a display of the animation in the instrument app.
- 6 Save and run the app.

The following topics contain more detailed steps for this workflow as an example. This example uses an `Aero.Animation` object.

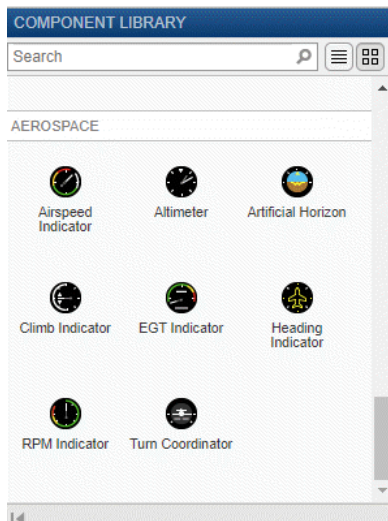
Start App Designer and Create a New App

- 1 Start App Designer. In the MATLAB Command Window, type:
`appdesigner`
- 2 In the App Designer welcome window, click **Blank App**. App Designer displays with a blank canvas.
- 3 To look at the blank app template, click **Code View**. Notice that the app contains a template with sections for app component properties, component initialization, and app creation and deletion.
- 4 To return to the canvas view, click **Design View**.

Drag Aerospace Components into the App

To add components to the blank canvas:

- 1 In the **Component Library**, navigate to Aerospace.



- 2 From the library, drag these aerospace components to the canvas:
 - Airspeed Indicator
 - Artificial Horizon
 - Turn Coordinator
 - Heading Indicator
 - Climb Indicator
 - Altimeter
- 3 This example uses an `Aero.Animation` object to visualize the flight status of an aircraft over time. To set the current time, add a time input device such as a slider or knob. As you change the time on the time input device, the flight instrument components and the animation window update to show the results. The example code provides further details.

For this example:

- Add a Slider component as a time input device.
 - To display the current time from the slider, edit the label of the slider. For example:
 - Change the label to `Time: 00.0 sec`.
 - Change the upper limit to 50.
- 4 Click **Code View** and note that the properties and component initialization sections now contain definitions for the new components. The code managed by App Designer is noneditable (grayed out).
 - 5 In the Property Inspector section on the right of the canvas, rename these components:
 - UIFigure component to `FlightInstrumentsFlightDataPlaybackUIFigure`
 - Slider component to `Time000secSlider`

Add Code to Load and Visualize Data for the App

This workflow assumes that you have started App Designer, created a blank app, and added aerospace components to the app.

- 1 In the code view for the app, place the cursor after the properties section and, in the Insert section, click **Callback**.

The Add Callback Function dialog box displays.

- 2 In the Add Callback Function dialog box:
 - a From the **Callback** list, select **StartupFcn**.
 - b In the Name parameter, enter a name for the startup function, for example `startupFcn`.

A callbacks section is added.

- 3 Add additional properties to the class for the simulation data and the animation object. Place your cursor just after the component properties section and, in the Insert section, click **Property** > **Public Property**. In the new properties template, add code so that it looks like this:

```
simdata % Saved flight data [time X Y Z phi theta psi]
animObj % Aero.Animation object
```

`simdata` is the saved flight data. `animObj` is the `Aero.Animation` object for the figure window.

- 4 To the `startupFcn` section, add code to the `startup` function that loads simulation data. For example, the `simdata.mat` file contains logged simulated flight trajectory data.

```
% Code that executes after component creation
function startupFcn(app)

    % Load saved flight status data
    savedData = load(fullfile(matlabroot, 'toolbox', 'aero', 'astdemos', 'simdata.mat'), 'simdata');
    yaw = savedData.simdata(:,7);
    yaw(yaw<0) = yaw(yaw<0)+2*pi; % Unwrap yaw angles
    savedData.simdata(:,7) = yaw;
    app.simdata = savedData.simdata; % Load saved flight status data
```

- 5 To visualize animation data, create an animation object. For example, after loading the simulation data:

- a Create an `Aero.Animation` object.

```
app.animObj = Aero.Animation;
```

- b Use the piper pa-24 comanche geometry for the animation object.

```
app.animObj.createBody('pa24-250_orange.ac','Ac3d'); % Piper PA-24 Comanche geometry
```

- c Use the data loaded previously, `app.simdata`, as the source for the animation object.

```
app.animObj.Bodies{1}.TimeseriesSourceType = 'Array6DoF'; % [time X Y Z phi theta psi]
app.animObj.Bodies{1}.TimeSeriesSource = app.simdata;
```

- d Initialize the camera and figure positions.

```
app.animObj.Camera.PositionFcn = @staticCameraPosition;
app.animObj.Figure.Position = [app.FlightInstrumentsFlightDataPlaybackUIFigure.Position(1)+625,...
    app.FlightInstrumentsFlightDataPlaybackUIFigure.Position(2),...
    app.FlightInstrumentsFlightDataPlaybackUIFigure.Position(3),...
    app.FlightInstrumentsFlightDataPlaybackUIFigure.Position(4)];
app.animObj.updateBodies(app.simdata(1,1)); % Initialize animation window at t=0
app.animObj.updateCamera(app.simdata(1,1));
```

- e Create and show the figure graphics object.

```
app.animObj.show();
```

Add Code to Trigger a Display of the Animation Object

This workflow assumes that you have added a startup function to the app to load simulation data and create an animation object. To trigger an update of the animation object and flight instruments:

- 1 In the code view for the app, add a callback for the slider. For example, navigate to the Property Inspector section and select `app.Time000secSlider`.
- 2 Enter a name for **valueChangingFcn**, for example, `Time000secSliderValueChanging`, and press **Enter**.

In the code view, App Designer adds a callback function `Time000secSliderValueChanging`.

- 3 Add code to display the current time in the slider label `Time000secSliderLabel`, for example:

```
% Display current time in slider component
t = event.Value;
app.Time000secSliderLabel.Text = sprintf('Time: %.1f sec', t);
```

- 4 Add code to compute data values for each flight instrument component corresponding with the selected time on the slider, for example:

```
% Find corresponding time data entry
k = find(app.simdata(:,1)<=t);
k = k(end);

app.Altimeter.Altitude = convlength(-app.simdata(k,4), 'm', 'ft');
app.HeadingIndicator.Heading = convang(app.simdata(k,7), 'rad', 'deg');
app.ArtificialHorizon.Roll = convang(app.simdata(k,5), 'rad', 'deg');
app.ArtificialHorizon.Pitch = convang(app.simdata(k,6), 'rad', 'deg');

if k>1
    % Estimate velocity and angular rates
    Vel = (app.simdata(k,2:4)-app.simdata(k-1,2:4))/(app.simdata(k,1)-app.simdata(k-1,1));
    rates = (app.simdata(k,5:7)-app.simdata(k-1,5:7))/(app.simdata(k,1)-app.simdata(k-1,1));

    app.AirspeedIndicator.Airspeed = convvel(sqrt(sum(Vel.^2)), 'm/s', 'kts');
    app.ClimbIndicator.ClimbRate = convvel(-Vel(3), 'm/s', 'ft/min');

    % Estimate turn rate and slip behavior
    app.TurnCoordinator.Turn = convangvel(rates(1)*sind(30) + rates(3)*cosd(30), 'rad/s', 'deg/s');
    app.TurnCoordinator.Slip = 1/(2*pi)*convang(atan(rates(3)*sqrt(sum(Vel.^2))/9.81)-app.simdata(k,5), 'rad', 'deg');
else
    % time = 0
    app.ClimbIndicator.ClimbRate = 0;
    app.AirspeedIndicator.Airspeed = 0;
    app.TurnCoordinator.Slip = 0;
    app.TurnCoordinator.Turn = 0;
end
```

- 5 Add code to update the animation window display, for example:

```
%% Update animation window display
app.animObj.updateBodies(app.simdata(k,1));
app.animObj.updateCamera(app.simdata(k,1));
```

Add Code to Close the Animation Window with UIFigure Window

This workflow assumes that you are ready to define the close function for the `FlightInstrumentsFlightDataPlaybackUIFigure` figure window.

- 1 Add a `CloseRequestFcn` function. In the code view for the app, place the cursor after the properties section for `FlightInstrumentsFlightDataPlaybackUIFigure` and, in the Insert section, click **Callback**.

The Add Callback Function dialog box displays.

- 2 In the Add Callback Function dialog box:
 - a From the **Callback** list, select `CloseRequestFcn`.
 - b In the Name parameter, enter a name for the close function, for example `FlightInstrumentsFlightDataPlaybackUIFigureCloseRequest`.

A callbacks section is added.

- 3 In the new callback template, add code to delete the animation object, such as:

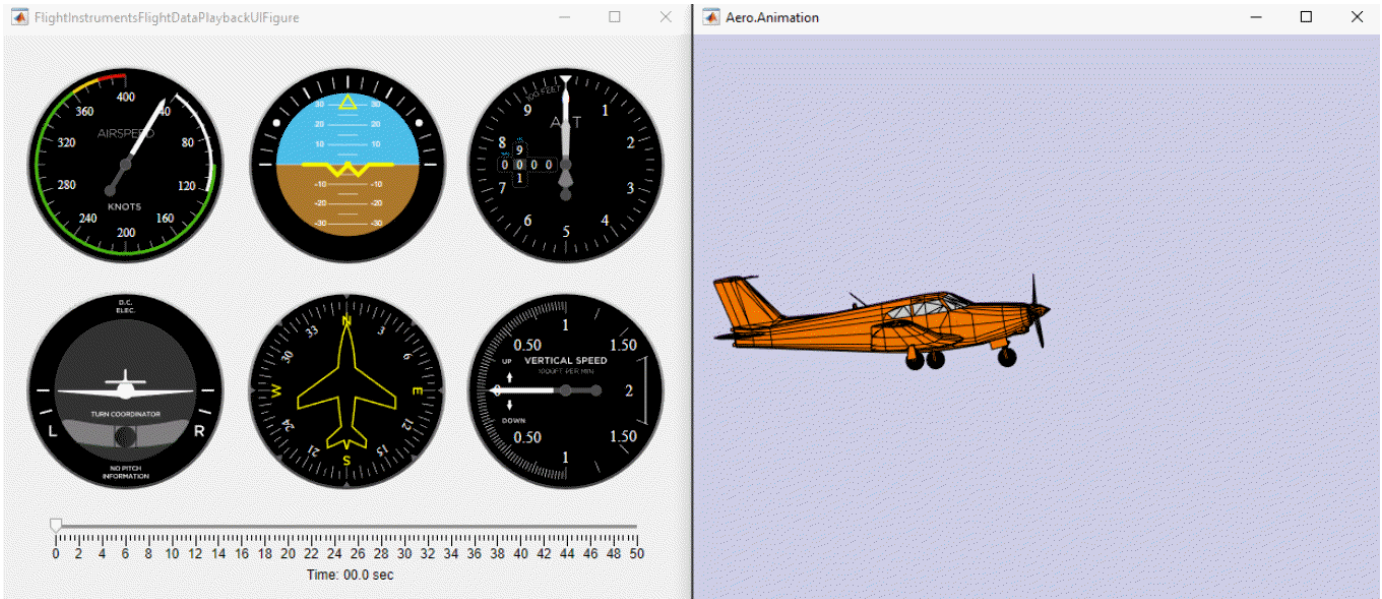
```
% Close animation figure with app
delete(app.animObj);
delete(app);
```

Save and Run the App

This workflow assumes that you have added code to close the uifigure window. To save and run the app:

- 1 Save the app with the file name `myFlightInstrumentsExample`. Note that this name is applied to the `classdef`.
- 2 Click **Run**.

After saving your changes, you can run the app from the App Designer window, or by typing its name (without the `.mlapp` extension) at the MATLAB Command Window. When you run the app from the command prompt, the file must be in the current folder or on the MATLAB path.



- 3 To visualize the saved flight data, change the slider position. Observe the flight instruments as the aircraft changes orientation in the animation window.

For a complete example, see “Aerospace Flight Instruments in App Designer” on page 5-114.

See Also

Functions

`uiaeroairspeed` | `uiaeroaltimeter` | `uiaeroclimb` | `uiaeroegt` | `uiaeroheading` | `uiaerohorizon` | `uiaerorpm` | `uiaeroturn` | `uiaxes` | `uifigure` | `uilabel` | `uislider`

Properties

`AirspeedIndicator` Properties | `Altimeter` Properties | `ArtificialHorizon` Properties | `ClimbIndicator` Properties | `EGTIndicator` Properties | `HeadingIndicator` Properties | `RPMIndicator` Properties | `TurnCoordinator` Properties

More About

- “Create and Configure Flight Instrument Component and an Animation Object” on page 2-49
- “Aerospace Flight Instruments in App Designer” on page 5-114
- “Flight Instruments”
- “Develop Apps Using App Designer”

Analyze Fixed-Wing Aircraft

To analyze fixed-wing aircraft in Aerospace Toolbox, use the `Aero.FixedWing` class and its supporting classes. These classes enable you to:

- Define aircraft dynamics
- Define aircraft dynamics from DATCOM files
- Perform static stability analyses
- Generate state-space representation with linearization methods

Suggested Workflow

As a guideline, consider this workflow when designing and building your fixed-wing aircraft with these classes:

To	Use
Define a fixed-wing aircraft.	<code>Aero.FixedWing</code> — <code>Aero.FixedWing</code> objects hold the main definition of fixed-wing aircraft. The object has a main set of body coefficients, which you can manipulate with the <code>Aero.FixedWing.Coefficient</code> object.
Define the condition (state) of a fixed-wing aircraft at an instance in time.	<code>Aero.FixedWing.State</code> — Use these objects when: <ul style="list-style-type: none"> • Your calculations require a specific aircraft state, such as those for forces and moments. • Gathering specific points of data from <code>Simulink.LookupTable</code> objects (requires a Simulink license).
To define data for any and all coefficients that describe the behavior of the aircraft.	<code>Aero.FixedWing.Coefficient</code> — <code>Aero.FixedWing.Coefficient</code> objects hold the data for all Coefficients that describe the behavior of the aircraft.
Define an aerodynamic surface on a fixed-wing aircraft.	<code>Aero.FixedWing.Surface</code> — <code>Aero.Aircraft.Surface</code> objects hold the definitions of the aircraft aerodynamic surfaces.
Define a thrust vector on a fixed-wing aircraft.	<code>Aero.FixedWing.Thrust</code> — <code>Aero.Aircraft.Thrust</code> Objects hold the definitions of the aircraft thrust.
Define the fixed-wing aircraft state environment.	<code>Aero.Aircraft.Environment</code> — <code>Aero.Aircraft.Environment</code> objects hold the fixed-wing aircraft state environment such as air temperature, pressure, density, gravity, and so forth.

To	Use
Define the properties for the fixed-wing aircraft.	<code>Aero.Aircraft.Properties</code> — <code>Aero.Aircraft.Properties</code> objects define common properties to maintain and define aircraft. Use this object throughout the fixed-wing aircraft design process.
To define the control states of a fixed-wing state.	<code>Aero.Aircraft.ControlState</code> — <code>Aero.Aircraft.ControlState</code> holds the definitions of the aircraft control surface deflection angles.

Static Stability Analysis

To perform static stability analysis of your fixed-wing aircraft:

- 1 Create a criteria table against which to perform static stability analysis.

To create a criteria table, use the `Aero.FixedWing.criteriaTable` method. This method creates a 6-by- N table, where N is the number of criteria variables.

- 2 To evaluate the changes in forces and moments after a perturbation as either greater than, equal to, or less than 0 using the matching entry in the criteria table, use `staticStability` method. The method uses this evaluation process:

- If the evaluation of a criteria is met, the aircraft is statically stable at that condition.
- If the evaluation of a criteria is not met, the aircraft is statically unstable at that condition.
- If the result of the perturbation is 0, the aircraft is statically neutral at that condition.

Use this method only in the preliminary design phase. The `staticStability` method does not perform a requirements-based analysis.

For an example of static stability analysis, see “Determine Nonlinear Dynamics and Static Stability of Fixed-Wing Aircraft” on page 5-128 .

Linear Analysis

To perform the linear analysis of the fixed-wing object at a given fixed-wing state, use the `linearize` method. This method linearizes a fixed-wing aircraft around an initial state and creates a state-space model for the linear analysis. To perform linear analysis:

- 1 Calculate the static stability of the fixed-wing aircraft using the `staticStability` method.
- 2 Linearize the fixed-wing aircraft using the `linearize` method.

For an example of fixed-wing aircraft linear analysis, see “Perform Controls and Static Stability Analysis with Linearized Fixed-Wing Aircraft” on page 5-115.

Linear analysis requires the Control System Toolbox™ license.

Examples

Aerospace Toolbox provides these examples to help you work with fixed-wing aircraft using the fixed-wing classes.

Action	Example
Create and analyze a fixed-wing aircraft in MATLAB using Cessna C182 geometry and coefficient data.	“Determine Nonlinear Dynamics and Static Stability of Fixed-Wing Aircraft” on page 5-128
Convert a fixed-wing aircraft to a linear time invariant (LTI) state-space model for linear analysis.	“Perform Controls and Static Stability Analysis with Linearized Fixed-Wing Aircraft” on page 5-115
Construct and define a custom state for a fixed-wing aircraft.	“Customize Fixed-Wing Aircraft with Additional Aircraft States” on page 5-122

See Also

`Aero.Aircraft.ControlState` | `Aero.Aircraft.Environment` |
`Aero.Aircraft.Properties` | `Aero.FixedWing` | `Aero.FixedWing.Coefficient` |
`Aero.FixedWing.State` | `Aero.FixedWing.Surface` | `Aero.FixedWing.Thrust`

Related Examples

- “Determine Nonlinear Dynamics and Static Stability of Fixed-Wing Aircraft” on page 5-128
- “Perform Controls and Static Stability Analysis with Linearized Fixed-Wing Aircraft” on page 5-115
- “Customize Fixed-Wing Aircraft with Additional Aircraft States” on page 5-122

Satellite Scenario Key Concepts

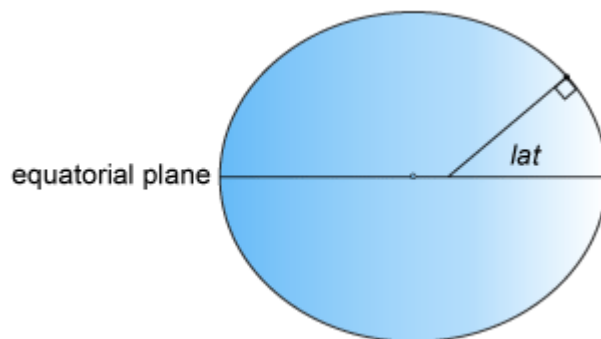
Aerospace Toolbox provides the ability to model and visualize satellites in orbit, compute access with ground stations, visualize and analyze communication links using the `satelliteScenario` object. This topic provides an overview of the technical terms frequently encountered in scenario visualization.

Coordinate Systems

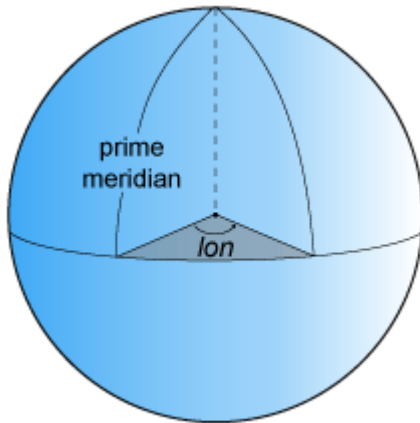
Geodetic Coordinates

A geodetic system uses the coordinates (lat, lon, h) to represent position relative to a reference ellipsoid. All geodetic coordinates in satellite scenario use the WGS84 ellipsoid as the reference ellipsoid. The coordinate origin of WGS 84 is meant to be located at the Earth's center of mass.

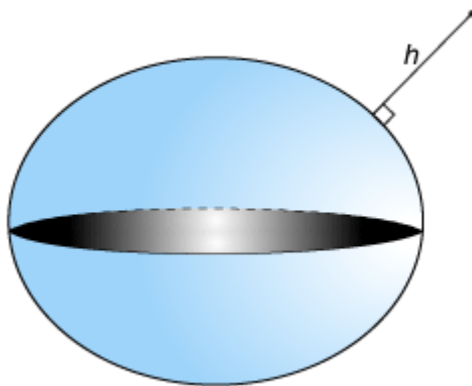
- lat , the latitude, originates at the equator. More specifically, the latitude of a point is the angle a normal to the ellipsoid at that point makes with the equatorial plane, which contains the center and equator of the ellipsoid. An angle of latitude is within the range $[-90^\circ, 90^\circ]$. Positive latitudes correspond to north and negative latitudes correspond to south.



- lon , the longitude, originates at the prime meridian. More specifically, the longitude of a point is the angle that a plane containing the ellipsoid center and the meridian containing that point makes with the plane containing the ellipsoid center and prime meridian. Positive longitudes are measured in a counterclockwise direction from a vantage point above the North Pole. Typically, longitude is within the range $[-180^\circ, 180^\circ]$ or $[0^\circ, 360^\circ]$.



- h , the ellipsoidal height, is measured along a normal of the reference spheroid.



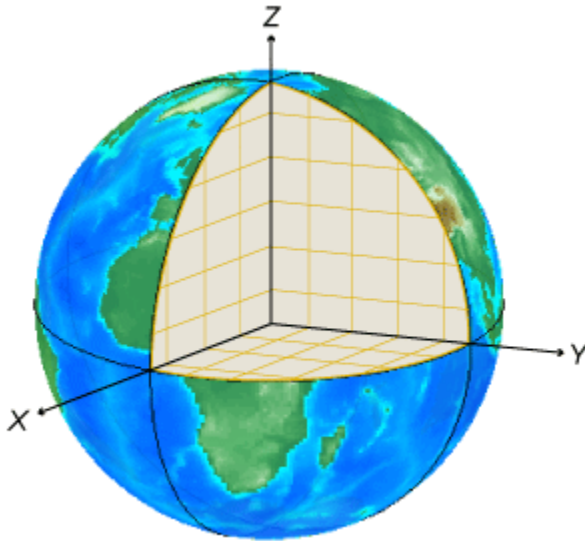
Earth-Centered Earth-Fixed Coordinates

An Earth-centered Earth-fixed (ECEF) system uses the Cartesian coordinates (X,Y,Z) to represent position relative to the center of the reference ellipsoid. The distance between the center of the ellipsoid and the center of the Earth depends on the reference ellipsoid.

- The positive X -axis intersects the surface of the ellipsoid at 0° latitude and 0° longitude, where the equator meets the prime meridian.
- The positive Y -axis intersects the surface of the ellipsoid at 0° latitude and 90° longitude.
- The positive Z -axis intersects the surface of the ellipsoid at 90° latitude and 0° longitude, the North Pole.

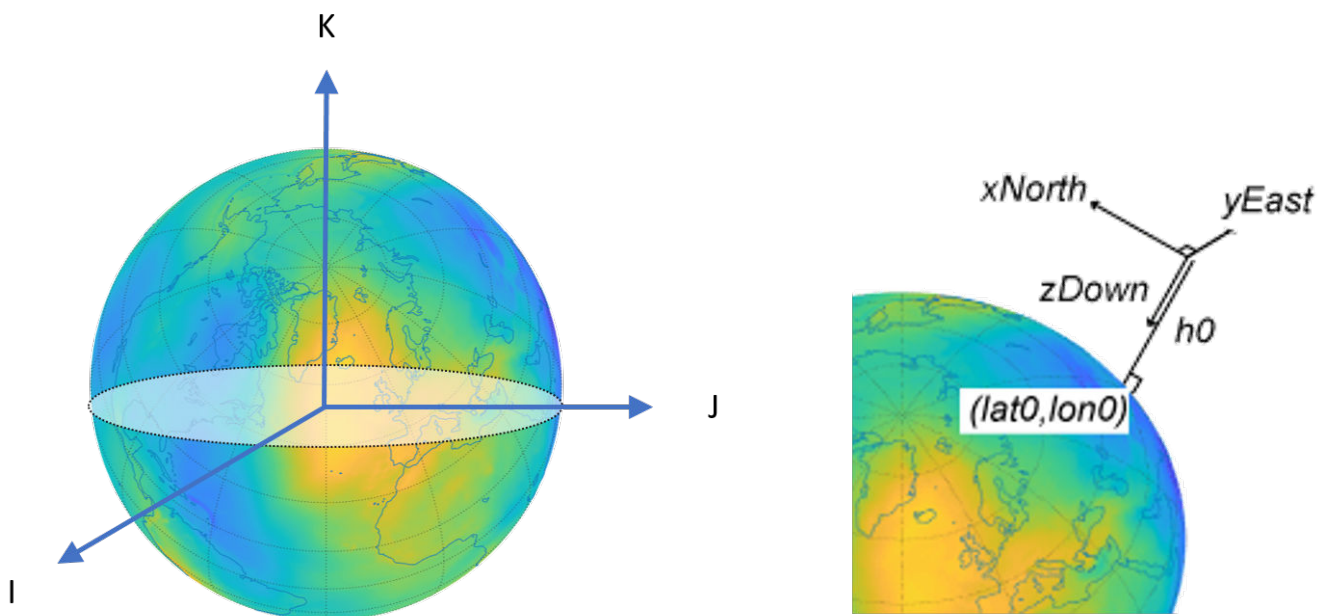
1

1. Alignment of boundaries and region labels are a presentation of the feature provided by the data vendors and do not imply endorsement by MathWorks®.



Frame of Reference and North East Down (NED) Frame

To describe a point in space, you need a frame of reference that does not rotate with respect to the stars. The Geocentric Celestial Reference Frame (GCRF), with the origin at the Earth's center and orthogonal vectors **I**, **J**, and **K**, is used as frame of reference while adding `satellite` objects to `satelliteScenario`. The fundamental plane is the **I, J** plane, which is closely aligned with the equator with a small offset, and **K** aligns closely with the north pole. You can describe the location of a satellite using a position vector and a velocity vector in the geocentric-equatorial coordinate system.



When referring to a satellite's position, velocity, acceleration, orientation and angular velocity, the coordinate system in which they are expressed should always be mentioned. Global systems such as GCRF and geodetic systems describe the position of an object using a triplet of coordinates. Local systems such as NED, and AER systems require two triplets of coordinates: one triplet describes the location of the origin, and the other triplet describes the location of the object with respect to the origin.

A north-east-down (NED) system uses the Cartesian coordinates ($x_{North}, y_{East}, z_{Down}$) to represent position relative to a local origin. The local origin is described by the geodetic coordinates ($lat0, lon0, h0$). Typically, the local origin of an NED system is above the surface of the Earth.

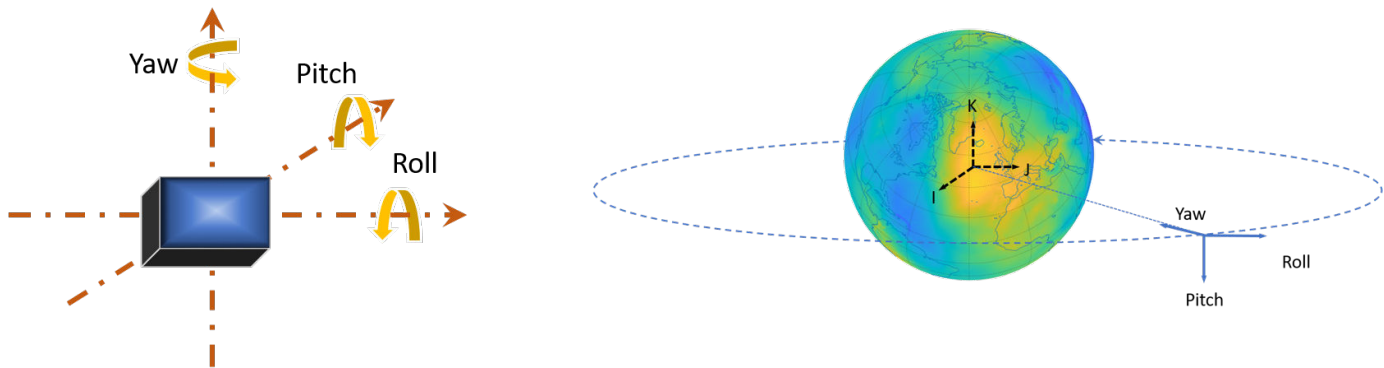
- The positive x_{North} -axis points north along the meridian of longitude containing $lon0$.
- The positive y_{East} -axis points east along the parallel of latitude containing $lat0$.
- The positive z_{Down} -axis points downward along the ellipsoid normal.

An NED coordinate system is commonly used to specify location relative to a moving satellite. Note that the coordinates are not fixed to the frame of the satellite.

Roll, Pitch, and Yaw

Three lines run through a satellite and intersect at right angles at the satellite's center of mass. These axes move with the satellite and rotate relative to the Earth along with the craft.

- Rotation around the front-to-back axis is called roll.
- Rotation around the side-to-side axis is called pitch.
- Rotation around the vertical axis is called yaw.



The yaw, pitch, and roll angles of satellites follow an ISO convention. These angles have positive clockwise directions when looking in the positive direction of the axes. Unless otherwise specified, by default Aerospace Toolbox uses yaw-pitch-roll rotation order for these angles.

Azimuth-Elevation-Range Coordinates

An azimuth-elevation-range (AER) system uses the spherical coordinates ($az, elev, range$) to represent position relative to a local origin. The local origin is described by the geodetic coordinates ($lat0, lon0, h0$). Azimuth, elevation, and slant range depend on a local Cartesian system, for example, an NED system.

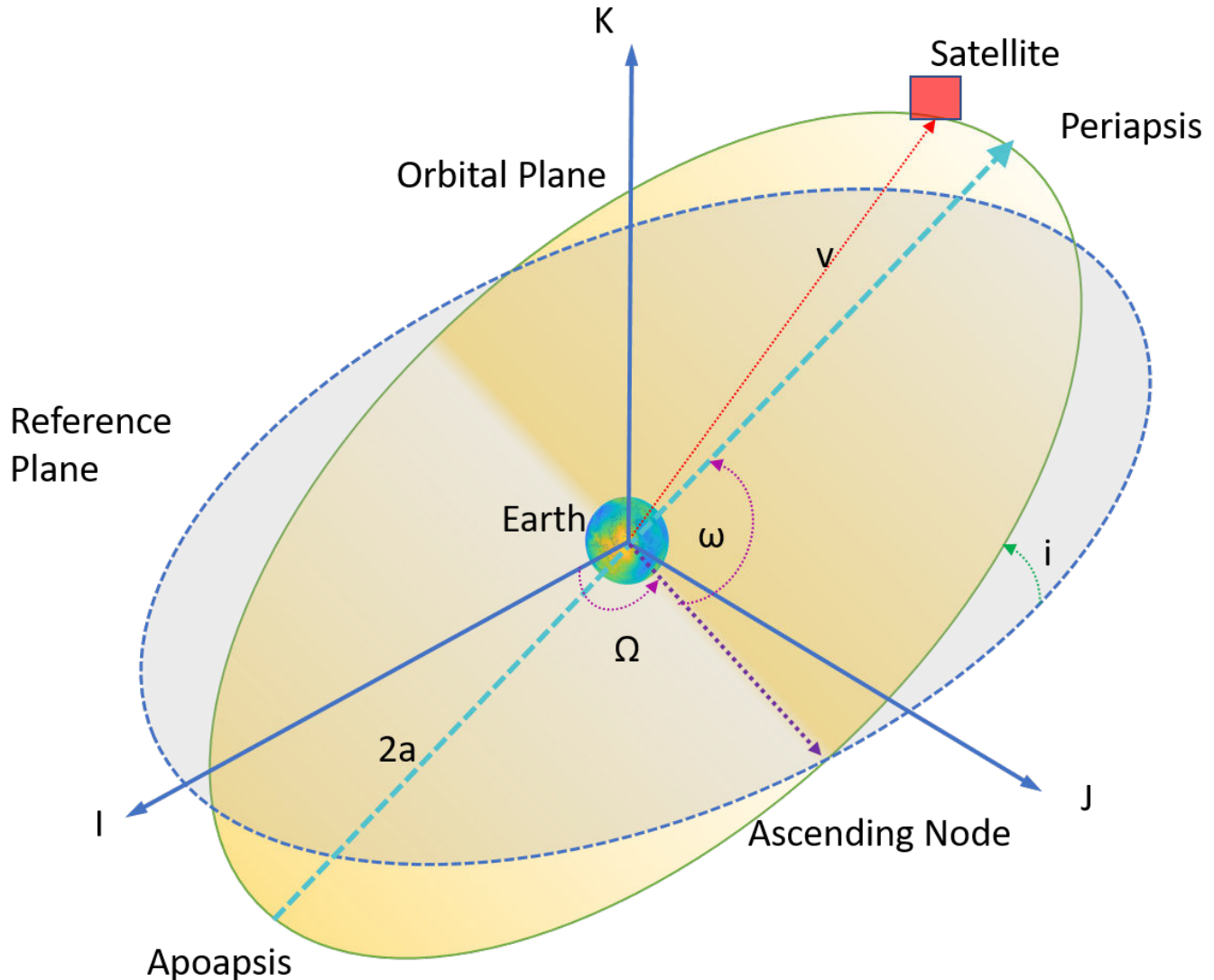
- az , the azimuth, is the clockwise angle in the $x_{East}-y_{North}$ plane from the positive y_{North} -axis to the projection of the object into the plane.

- *elev*, the elevation, is the angle from the *xEast-yNorth* plane to the object.
- *range*, the slant range, is the Euclidean distance between the object and the local origin.



Orbital Elements

Orbital elements are parameters required to uniquely identify a specific orbit. It takes at least six parameters to uniquely define an orbit and a satellite's position within the orbit. Three of the parameters describe what the orbital plane looks like and the position of the satellite in the ellipse, and the other three parameters describe how that plane is oriented in the celestial inertial reference frame and where the satellite is in that plane. These six parameters are called the Keplerian elements or orbital elements.



In this diagram, the orbital plane (yellow) intersects a reference plane (gray). For Earth-orbiting satellites, the reference plane is usually the I-J plane of the Geocentric Celestial Reference Frame (GCRF).

Two elements define the shape and size of the ellipse:

- **Eccentricity (e)** — Shape of the ellipse, describing how elongated it is compared to a circle.
- **Semimajor axis (a)** — Sum of the periapsis and apoapsis distances divided by two. Periapsis is the point at which an orbiting object is closest to the center of mass of the body it is orbiting. Apoapsis is the point at which an orbiting object is farthest away from the center of mass of the body it is orbiting. For classic two-body orbits, the semimajor axis is the distance between the centers of the bodies.

The next two elements define the orientation of the orbital plane in which the ellipse is embedded:

- **Inclination (i)** — Vertical tilt of the ellipse with respect to the reference plane, measured at the ascending node (where the orbit passes upward through the reference plane, the green angle i in the diagram). Tilt angle is measured perpendicular to line of intersection between orbital plane and reference plane. Any three points on an ellipse will define the ellipse orbital plane.

Starting with an equatorial orbit, the orbital plane can be tilted up. The angle tilted up from the equator is referred to as the inclination angle, i . Since the center of the earth must always be in the orbital plane, the point in the orbit where the satellite passes the equator on its way up is referred to as the ascending node, and the point where the satellite passes the equator on the way down is the descending node. Drawing a line through these two points on the equator is what defines the line of nodes.

- **Right ascension of ascending node (Ω)** — Horizontal orientation of the ascending node of the ellipse (where the orbit passes upward through the reference plane) with respect to the reference frame's I axis.

The rotation of the right ascension of the ascending node (RAAN) can be any number between 0 and 360°.

The remaining two elements are as follows:

- **Argument of periapsis (ω)** — Orientation of the ellipse in the orbital plane, as an angle measured from the ascending node to the periapsis.
- **True Anomaly (v)** — Position of the orbiting body along the ellipse at a specific time. The satellite's position on the path is measured counter-clockwise from periapsis and is called the true anomaly, v .

Two Line Element (TLE) Files

Aerospace Toolbox accepts Two Line Element (TLE) files as inputs to `satellite`. To download TLE files, visit the Space track website.

A two-line element set is a data format encoding a list of orbital elements of an Earth orbiting object for a given point in time, the *epoch*. Orbital elements parameters can be encoded as text in a number of formats. The most common of them is the NASA/NORAD "two-line elements" format. As commonly used today, each satellite gets three lines - one line containing the satellite's name, followed by the standard two lines of elements.

Data for each satellite consists of three lines.

Satellite 1

```
1 25544U 98067A 04236.56031392 .00020137 00000-0 16538-3 0 9993
2 25544 51.6335 344.7760 0007976 126.2523 325.9359 15.70406856328906
```

- Line 1 is a eleven-character satellite name.
- Line 2 and 3 are the standard Two-Line element set format identical to that used by NORAD and NASA.

Column	Description	Example
1	Line Number	1
3 – 7	Satellite Number	25544
8	Elset Classification	U
10 – 17	International Designator	98067A
19 – 32	Element Set Epoch (UTC)	04236.56031392
34 – 43	First derivative of the Mean Motion with respect to time	.00020137
45 – 52	Second derivative of the Mean Motion with respect to Time (decimal point assumed)	00000-0
54 – 61	BSTAR Drag Term.	16538-3
63	Element set type	0
65 – 68	Element number	999
69	Check Sum (Modulo 10)	3

Column	Description	Examples
1	Line Number of Element Data	2
3 – 7	Satellite Number	25544
9 – 16	Inclination [Degrees]	51.6335
18 – 25	Right Ascension of the Ascending Node [Degrees]	344.7760
27 – 33	Eccentricity (Leading decimal point assumed)	0007976
35 – 42	Argument of Perigee [Degrees]	126.2523
44 – 51	Mean Anomaly [Degrees]	325.9359
53 – 63	Mean Motion [Revs per day]	15.70406856
64 – 68	Revolution number at epoch [Revs]	32890
69	Check Sum (Modulo 10)	6

Depending on the application and object orbit, the data derived from TLEs older than 30 days can become unreliable. Orbital positions can be calculated from TLEs through the SGP4 and SDP4 algorithms.

References

- [1] "HSF - Orbital Elements." Accessed November 30, 2020. <https://spaceflight.nasa.gov/realdatal/elements/graphs.html>.

[2] "CelesTrak: 'FAQs: Two-Line Element Set Format,'" March 26, 2016. <https://web.archive.org/web/20160326061740/http://celestrak.com/columns/v04n03/>.

See Also

Objects

access | groundStation | satellite | satelliteScenario | satelliteScenarioViewer

Functions

play | show

More About

- "Satellite Scenario Overview" on page 2-69

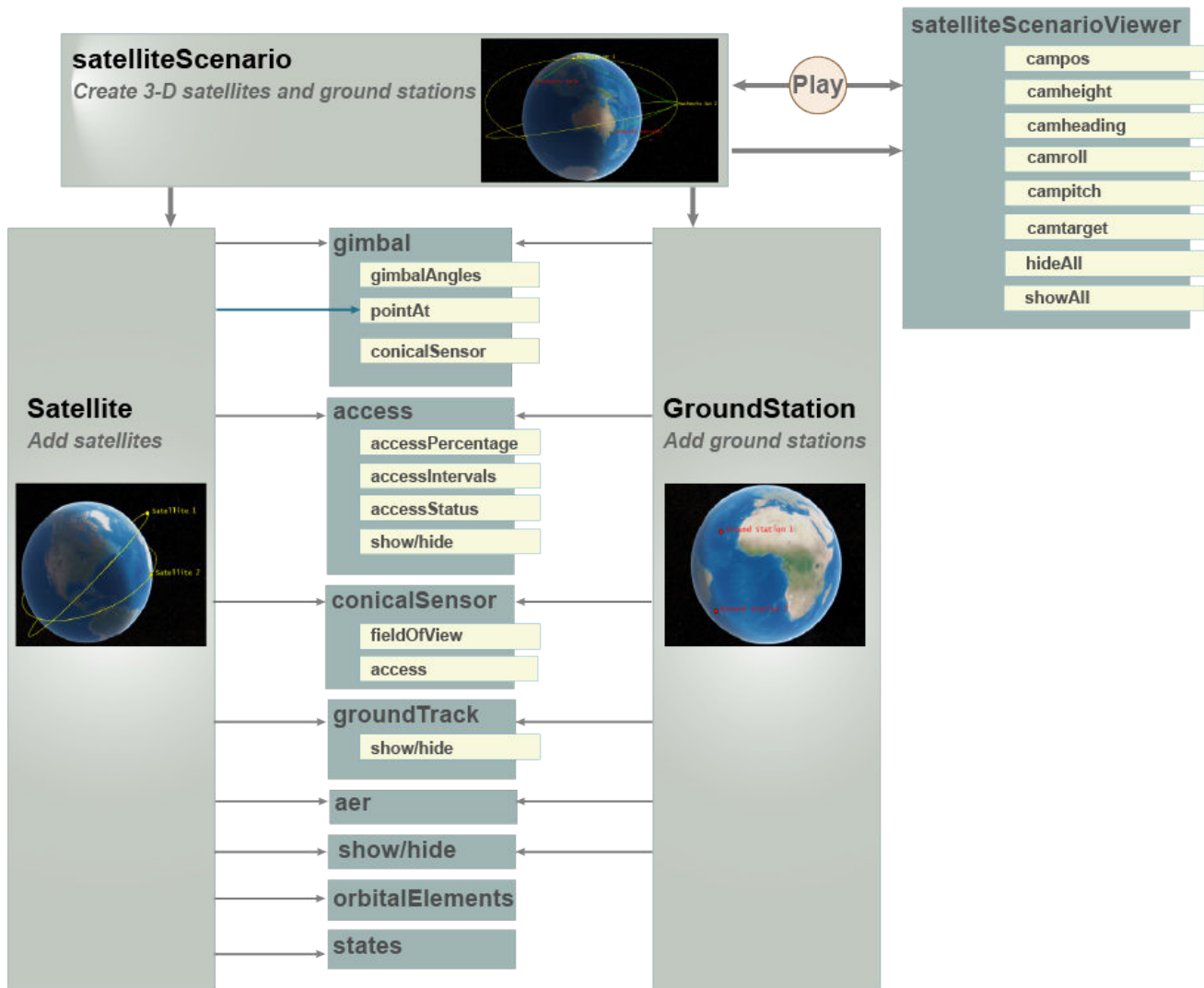
Satellite Scenario Overview

You can build a complete satellite scenario simulation using functions and objects. You can extend satellite scenarios for detailed communication simulations using Satellite Communications Toolbox. The workflow for satellite scenario simulation consists of four main components. These components are

- `satelliteScenario` represents a 3-D arena consisting of satellites, ground stations, and the interactions between them. Use this object to model satellite constellations, model ground station networks, perform access analyses between the satellites and ground stations, and visualize the results.
- `satellite` adds satellites to the scenario using two line element (TLE) files or orbital elements. For more details on orbital elements and TLE files, see “Two Line Element (TLE) Files” on page 2-66.
- `groundStation` adds ground stations to the scenario using default parameters or the specified latitude and longitude.
- `satelliteScenarioViewer` creates a 3D viewer for the scenario.
- `play` simulates the satellite scenario and plays the results in the visualization window specified by `satelliteScenarioViewer`.

Many of the methods included in the flowchart are created by multiple objects.

- `access` is created by `satellite`, `groundStation`, and `conicalSensor`.
- `show` and `hide` are created by `satellite`, `groundStation`, `groundTrack` and `access`.
- `conicalSensor` is created by `satellite`, `groundStation` and `gimbal`.



See Also

Objects

access | conicalSensor | groundStation | satellite | satelliteScenario | satelliteScenarioViewer

Functions

hide | play | show

More About

- “Satellite Scenario Key Concepts” on page 2-61

Add-On for Ephemeris and Geoid Data Support

Add Ephemeris and Geoid Data for Aerospace Products

Add ephemeris and/or geoid data to use it with the Aerospace Toolbox functions and Aerospace Blockset blocks. You can add data for these functions and blocks.

Aerospace Toolbox Functions	Aerospace Blockset Blocks
geoidheight	Geoid Height
Note Only for the EGM2008 Geopotential Model. Aerospace Toolbox provides EGM96 Geopotential Model data.	Note Only for the EGM2008 Geopotential Model. Aerospace Toolbox provides EGM96 Geopotential Model data.
earthNutation	Earth Nutation
moonLibration	Moon Libration
planetEphemeris	Planetary Ephemeris

To add ephemeris and geoid data for these functions and blocks.

- 1 In a MATLAB Command Window, type:

```
aeroDataPackage
```

The Add-On Explorer starts.
- 2 Select the data you want to add, for example:
 - Geoid Data for Aerospace Toolbox
 - Ephemeris Data for Aerospace Toolbox
- 3 On the data page, click the **Install** button.

Note You must have write privileges for the folder to which you are adding data.

To check for updates, repeat this process when a new version of MATLAB software is released. You can also check for updates between releases using this process.

Functions

access

Package: satelliteScenario

Add access analysis objects to satellite scenario

Syntax

```
access(obj1,...,objN)
ac = access(obj1,...,objN)
ac = access( __ , 'Viewer', Viewer)
```

Description

`access(obj1,...,objN)` adds Access objects defined by `obj1`, `obj2`, and so on.

`ac = access(obj1,...,objN)` returns a handle to the added access objects. The length of the vector corresponds to the number of Access objects added to the handle to the added access.

`ac = access(__ , 'Viewer', Viewer)` sets the viewer in addition to any input argument combination from previous syntaxes. For example, 'Viewer', v1 picks the viewer v1.

Examples

Add Ground stations to Scenario and Visualize Access Intervals

Create satellite scenario and add ground stations from latitudes and longitudes.

```
startTime = datetime(2020, 5, 1, 11, 36, 0);
stopTime = startTime + days(1);
sampleTime = 60;
sc = satelliteScenario(startTime, stopTime, sampleTime);
lat = [10];
lon = [-30];
gs = groundStation(sc, lat, lon);
```

Add satellites using Keplerian elements.

```
semiMajorAxis = 10000000;
eccentricity = 0;
inclination = 10;
rightAscensionOfAscendingNode = 0;
argumentOfPeriapsis = 0;
trueAnomaly = 0;
sat = satellite(sc, semiMajorAxis, eccentricity, inclination, ...
    rightAscensionOfAscendingNode, argumentOfPeriapsis, trueAnomaly);
```

Add access analysis to the scenario and obtain the table of intervals of access between the satellite and the ground station.

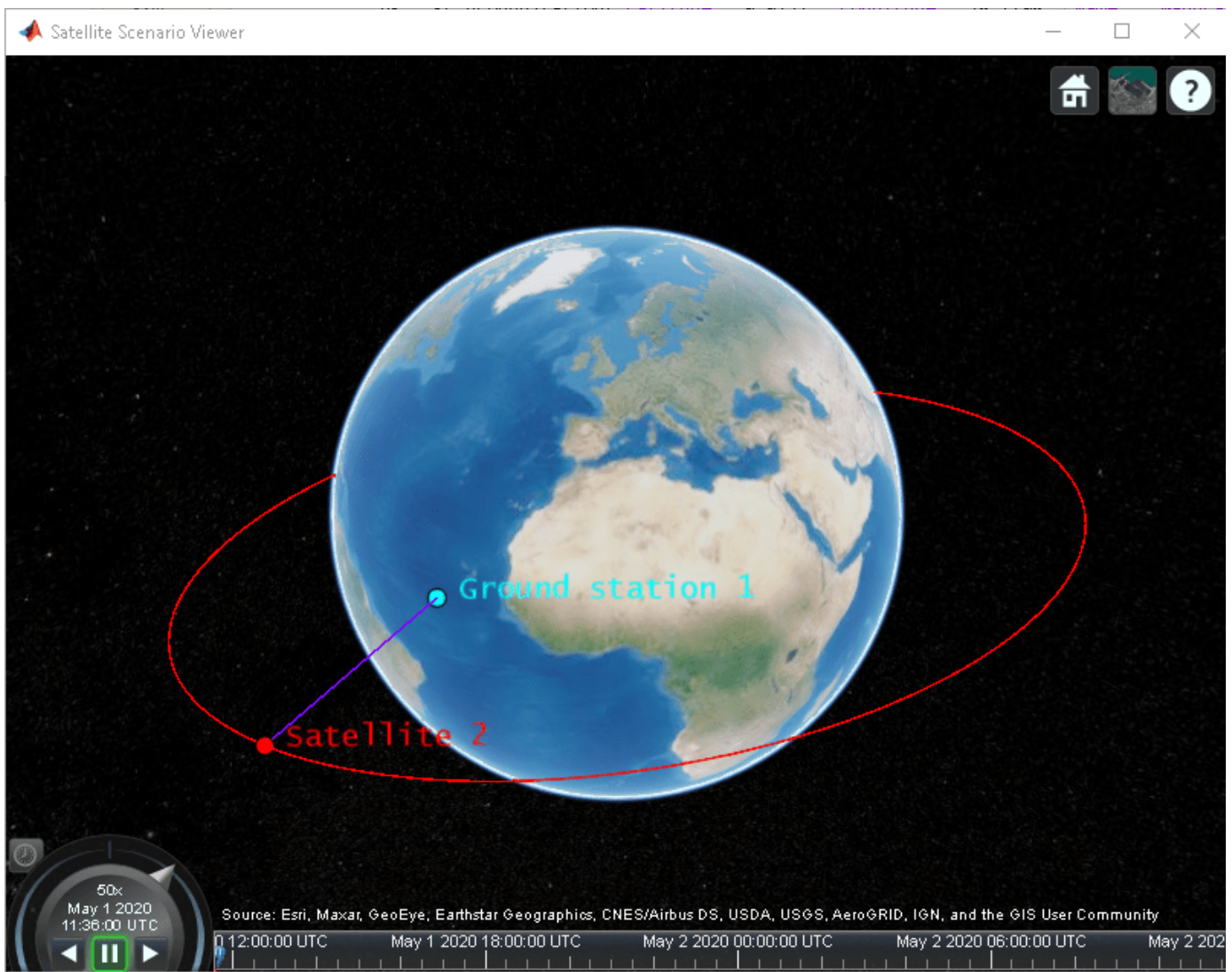
```
ac = access(sat, gs);
intvls = accessIntervals(ac)
```

intvls=8x8 table
Source

Source	Target	IntervalNumber	StartTime	EndTime
"Satellite 2"	"Ground station 1"	1	01-May-2020 11:36:00	01-May-2020
"Satellite 2"	"Ground station 1"	2	01-May-2020 14:20:00	01-May-2020
"Satellite 2"	"Ground station 1"	3	01-May-2020 17:27:00	01-May-2020
"Satellite 2"	"Ground station 1"	4	01-May-2020 20:34:00	01-May-2020
"Satellite 2"	"Ground station 1"	5	01-May-2020 23:41:00	02-May-2020
"Satellite 2"	"Ground station 1"	6	02-May-2020 02:50:00	02-May-2020
"Satellite 2"	"Ground station 1"	7	02-May-2020 05:59:00	02-May-2020
"Satellite 2"	"Ground station 1"	8	02-May-2020 09:06:00	02-May-2020

Play the scenario to visualize the ground stations.

play(sc)



Input Arguments

obj1, ..., objN — Satellite, ground station, or conical sensor

Satellite object | GroundStation object | ConicalSensor object

Satellite, GroundStation, or ConicalSensors object. These objects must belong to the same satelliteScenario object. The function adds the access analysis object to the Accesses property of obj1, ..., objN.

Name-Value Pair Arguments

Specify optional comma-separated pairs of Name, Value arguments. Name is the argument name and Value is the corresponding value. Name must appear inside quotes. You can specify several name and value pair arguments in any order as Name1, Value1, ..., NameN, ValueN.

Example: 'Viewer', v1 picks the viewer v1.

Viewer — Satellite scenario viewer

(default) | row vector of all viewer objects | row vector of satelliteScenarioViewer objects

Satellite scenario viewer, specified as a row vector of satelliteScenarioViewer objects.

Data Types: char | string

Output Arguments

ac — Access analysis

Access object scalar

Access analysis between input objects, returned as an Access object scalar.

See Also

Objects

satelliteScenario | satelliteScenarioViewer

Functions

conicalSensor | groundStation | hide | play | show

Topics

“Satellite Scenario Key Concepts” on page 2-61

Introduced in R2021a

Access

Access analysis object belonging to scenario

Description

The Access object defines an access analysis object belonging to a `Satellite`, `GroundStation` or `ConicalSensor`.

Creation

You can create an Access object using the `access` object function of `GroundStation` or `Satellite`.

Properties

Sequence — Satellite, ground station, or conical sensor ID

row vector of positive real numbers

You can set this property only when calling `access`. After you call `access`, this property is read-only.

Satellite, ground station, or conical sensor ID defining the nodes of access analysis.

LineWidth — Visual width of access analysis object

1 (default) | scalar

Visual width of access analysis object in pixels, specified as a scalar in the range (0, 10).

The line width cannot be thinner than the width of a pixel. If you set the line width to a value that is less than the width of a pixel on your system, the line displays as one pixel wide.

LineColor — Color of analysis line

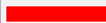




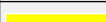


[0.5 0 1] (default) | RGB triplet | hexadecimal color code | color name | short name

Color of access analysis line, specified as an RGB triplet, hexadecimal color code, a color name, or a short name.

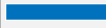






For a custom color, specify an RGB triplet or a hexadecimal color code.

- An RGB triplet is a three-element row vector whose elements specify the intensities of the red, green, and blue components of the color. The intensities must be in the range [0, 1]; for example, [0.4 0.6 0.7].
- A hexadecimal color code is a character vector or a string scalar that starts with a hash symbol (#) followed by three or six hexadecimal digits, which can range from 0 to F. The values are not case sensitive. Thus, the color codes '#FF8800', '#ff8800', '#F80', and '#f80' are equivalent.

Alternatively, you can specify some common colors by name. This table lists the named color options, the equivalent RGB triplets, and hexadecimal color codes.

Color Name	Short Name	RGB Triplet	Hexadecimal Color Code	Appearance
'red'	'r'	[1 0 0]	'#FF0000'	
'green'	'g'	[0 1 0]	'#00FF00'	
'blue'	'b'	[0 0 1]	'#0000FF'	
'cyan'	'c'	[0 1 1]	'#00FFFF'	
'magenta'	'm'	[1 0 1]	'#FF00FF'	
'yellow'	'y'	[1 1 0]	'#FFFF00'	
'black'	'k'	[0 0 0]	'#000000'	
'white'	'w'	[1 1 1]	'#FFFFFF'	
'none'	Not applicable	Not applicable	Not applicable	No color

Here are the RGB triplets and hexadecimal color codes for the default colors MATLAB uses in many types of plots.

RGB Triplet	Hexadecimal Color Code	Appearance
[0 0.4470 0.7410]	'#0072BD'	
[0.8500 0.3250 0.0980]	'#D95319'	
[0.9290 0.6940 0.1250]	'#EDB120'	
[0.4940 0.1840 0.5560]	'#7E2F8E'	
[0.4660 0.6740 0.1880]	'#77AC30'	
[0.3010 0.7450 0.9330]	'#4DBEEE'	
[0.6350 0.0780 0.1840]	'#A2142F'	

Example: 'blue'

Example: [0 0 1]

Example: '#0000FF'

Object Functions

show	Show object in satellite scenario viewer
accessStatus	Status of access between first and last node defining access analysis
accessIntervals	Intervals during which access status is true
accessPercentage	Percentage of time when access exists between first and last node defining access analysis
hide	Hides satellite scenario entity from viewer

Examples

Add Ground stations to Scenario and Visualize Access Intervals

Create satellite scenario and add ground stations from latitudes and longitudes.

```

startTime = datetime(2020, 5, 1, 11, 36, 0);
stopTime = startTime + days(1);
sampleTime = 60;
sc = satelliteScenario(startTime, stopTime, sampleTime);
lat = [10];
lon = [-30];
gs = groundStation(sc, lat, lon);

```

Add satellites using Keplerian elements.

```

semiMajorAxis = 10000000;
eccentricity = 0;
inclination = 10;
rightAscensionOfAscendingNode = 0;
argumentOfPeriapsis = 0;
trueAnomaly = 0;
sat = satellite(sc, semiMajorAxis, eccentricity, inclination, ...
    rightAscensionOfAscendingNode, argumentOfPeriapsis, trueAnomaly);

```

Add access analysis to the scenario and obtain the table of intervals of access between the satellite and the ground station.

```

ac = access(sat, gs);
intvls = accessIntervals(ac)

```

intvls=8x8 table

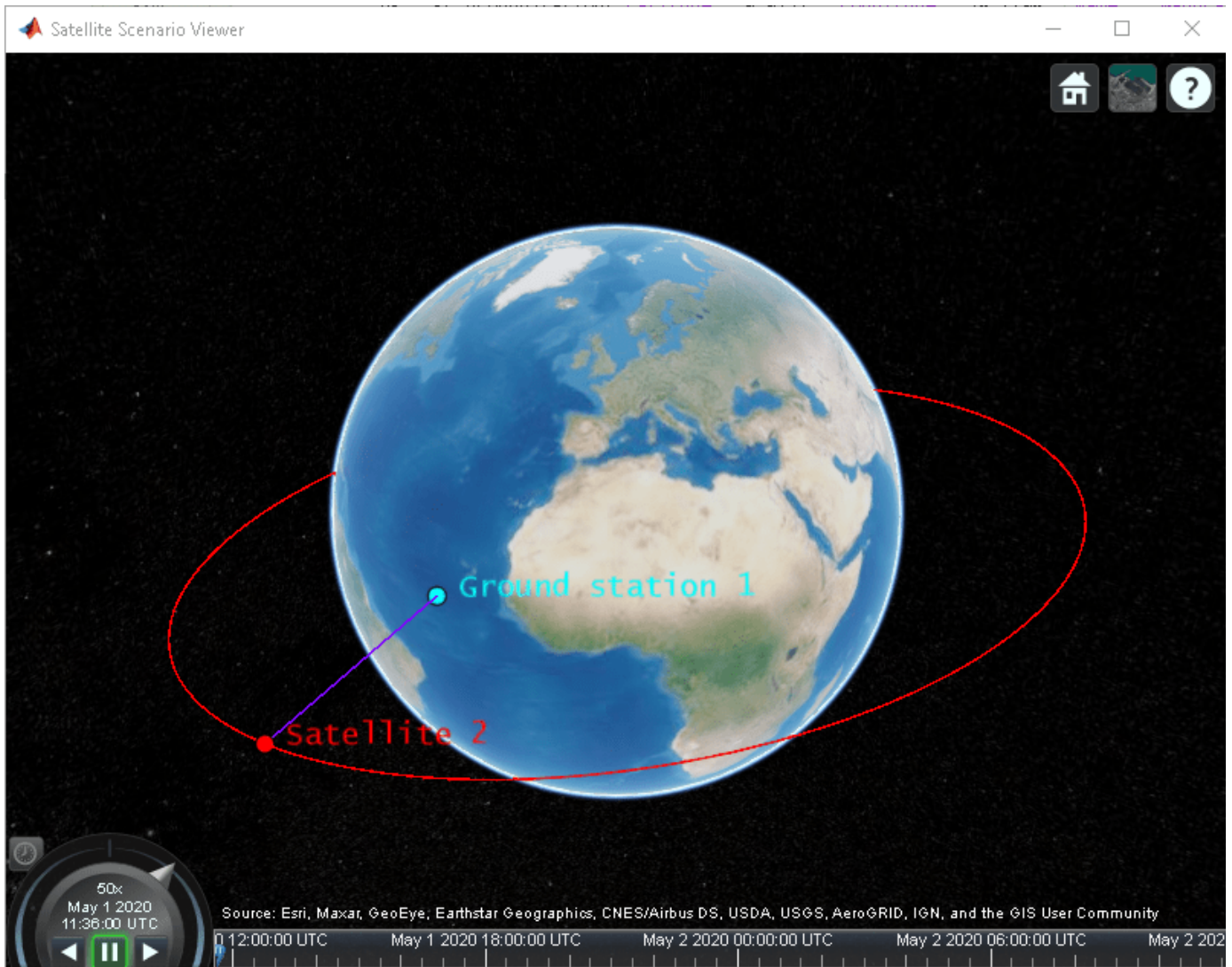
Source	Target	IntervalNumber	StartTime	EndTime
"Satellite 2"	"Ground station 1"	1	01-May-2020 11:36:00	01-May-2020
"Satellite 2"	"Ground station 1"	2	01-May-2020 14:20:00	01-May-2020
"Satellite 2"	"Ground station 1"	3	01-May-2020 17:27:00	01-May-2020
"Satellite 2"	"Ground station 1"	4	01-May-2020 20:34:00	01-May-2020
"Satellite 2"	"Ground station 1"	5	01-May-2020 23:41:00	02-May-2020
"Satellite 2"	"Ground station 1"	6	02-May-2020 02:50:00	02-May-2020
"Satellite 2"	"Ground station 1"	7	02-May-2020 05:59:00	02-May-2020
"Satellite 2"	"Ground station 1"	8	02-May-2020 09:06:00	02-May-2020

Play the scenario to visualize the ground stations.

```

play(sc)

```



See Also

Objects

`satelliteScenario` | `satelliteScenarioViewer`

Functions

`conicalSensor` | `groundStation` | `hide` | `play` | `satellite` | `show`

Topics

“Satellite Scenario Key Concepts” on page 2-61

Introduced in R2021a

accessIntervals

Package: satelliteScenario

Intervals during which access status is true

Syntax

```
int = accessIntervals(ac)
```

Description

`int = accessIntervals(ac)` returns a table of intervals during which the access status corresponding to each access object in the input vector is true.

Examples

Add Ground stations to Scenario and Visualize Access Intervals

Create satellite scenario and add ground stations from latitudes and longitudes.

```
startTime = datetime(2020, 5, 1, 11, 36, 0);
stopTime = startTime + days(1);
sampleTime = 60;
sc = satelliteScenario(startTime, stopTime, sampleTime);
lat = [10];
lon = [-30];
gs = groundStation(sc, lat, lon);
```

Add satellites using Keplerian elements.

```
semiMajorAxis = 10000000;
eccentricity = 0;
inclination = 10;
rightAscensionOfAscendingNode = 0;
argumentOfPeriapsis = 0;
trueAnomaly = 0;
sat = satellite(sc, semiMajorAxis, eccentricity, inclination, ...
    rightAscensionOfAscendingNode, argumentOfPeriapsis, trueAnomaly);
```

Add access analysis to the scenario and obtain the table of intervals of access between the satellite and the ground station.

```
ac = access(sat, gs);
intvls = accessIntervals(ac)
```

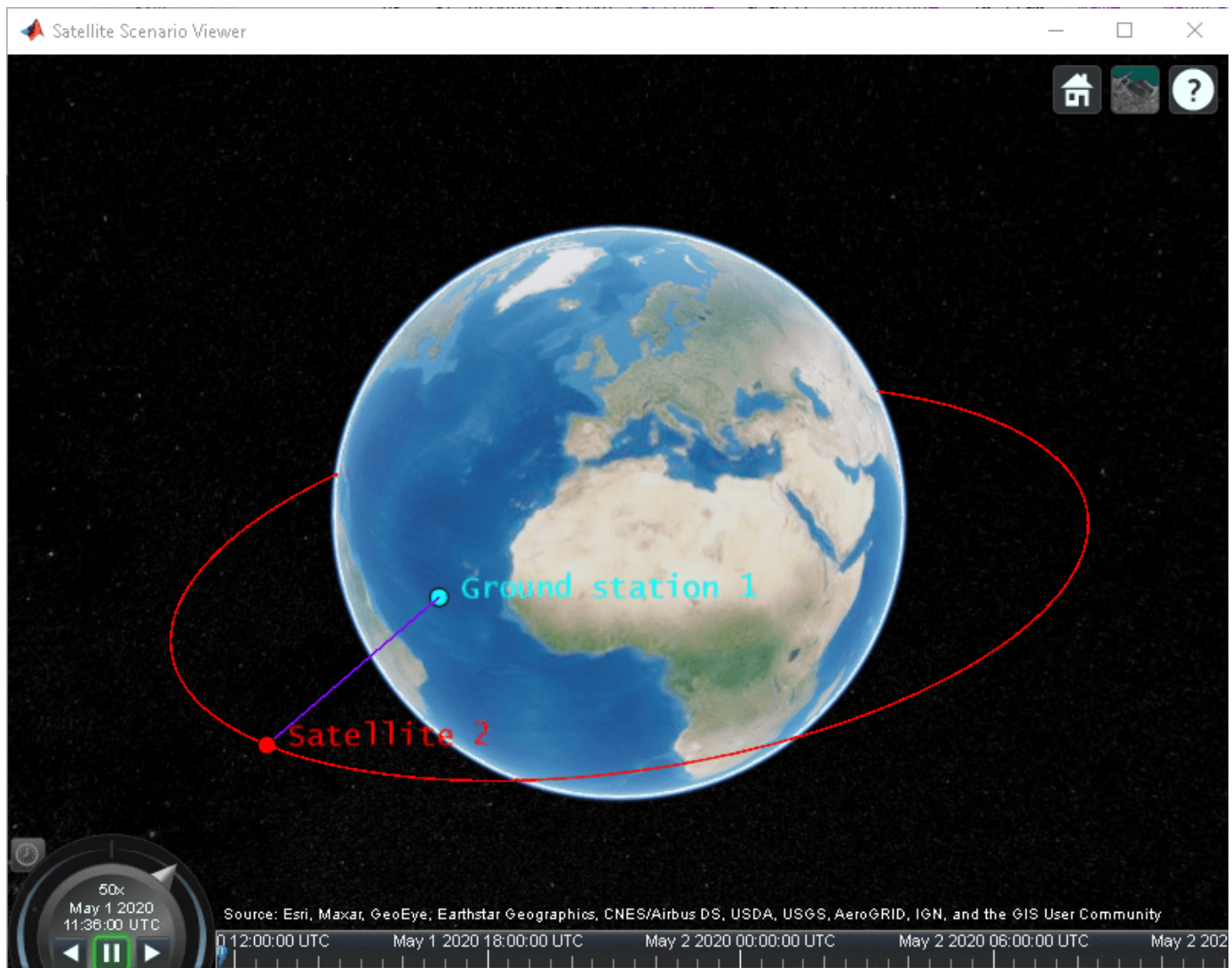
`intvls=8×8 table`

Source	Target	IntervalNumber	StartTime	EndTime
"Satellite 2"	"Ground station 1"	1	01-May-2020 11:36:00	01-May-2020
"Satellite 2"	"Ground station 1"	2	01-May-2020 14:20:00	01-May-2020

"Satellite 2"	"Ground station 1"	3	01-May-2020 17:27:00	01-May-2020
"Satellite 2"	"Ground station 1"	4	01-May-2020 20:34:00	01-May-2020
"Satellite 2"	"Ground station 1"	5	01-May-2020 23:41:00	02-May-2020
"Satellite 2"	"Ground station 1"	6	02-May-2020 02:50:00	02-May-2020
"Satellite 2"	"Ground station 1"	7	02-May-2020 05:59:00	02-May-2020
"Satellite 2"	"Ground station 1"	8	02-May-2020 09:06:00	02-May-2020

Play the scenario to visualize the ground stations.

`play(sc)`



Input Arguments

ac – Access analysis

row vector of Access objects

Access analysis, specified as a row vector of a Access objects.

Outputs Arguments

int — Intervals during which access is true

table

Intervals during which access is true, returned as a table.

Each row of the table denotes a specific interval, and the columns of the table are named `Source`, `Target`, `IntervalNumber`, `StartTime`, `EndTime`, `Duration` (in seconds), `StartOrbit`, and `EndOrbit`. `Source` and `Target` are the names of the first and last node, respectively, defining the access analysis.

- If `Source` is a satellite or an object that is directly or indirectly attached to a satellite, then `StartOrbit` and `EndOrbit` correspond to the satellite associated with `Source`.
- If `Target` is a satellite or an object that is directly or indirectly attached to a satellite, then `StartOrbit` and `EndOrbit` correspond to the satellite associated with `Target`. Otherwise, `StartOrbit` and `EndOrbit` are NaN because they are associated with ground stations.

See Also

Objects

`satelliteScenario` | `satelliteScenarioViewer`

Functions

`conicalSensor` | `groundStation` | `hide` | `play` | `show`

Topics

“Satellite Scenario Key Concepts” on page 2-61

Introduced in R2021a

accessPercentage

Package: satelliteScenario

Percentage of time when access exists between first and last node defining access analysis

Syntax

```
ap = accessPercentage(ac)
```

Description

`ap = accessPercentage(ac)` returns the percentages of time from start time to stop time of the satellite scenario when access exists between the first and last node of each access object in the input vector.

Input Arguments

ac — Access analysis

row vector of Access objects

Access analysis, specified as a row vector of a Access objects.

Outputs Arguments

ap — Access percentage

row vector of nonnegative numbers

Access percentage, returned as a row vector of nonnegative numbers.

See Also

Objects

satelliteScenario | satelliteScenarioViewer

Functions

conicalSensor | groundStation | hide | play | show

Topics

“Satellite Scenario Key Concepts” on page 2-61

Introduced in R2021a

accessStatus

Package: satelliteScenario

Status of access between first and last node defining access analysis

Syntax

```
s = accessStatus(ac)
s = accessStatus(ac,timeIn)
[s,timeOut] = accessStatus( ___ )
```

Description

`s = accessStatus(ac)` returns the access status history between the first and last node defining each access object in the input vector.

`s = accessStatus(ac,timeIn)` returns the status of each access analysis object at the specified datetime in `timeIn`.

`[s,timeOut] = accessStatus(___)` returns the status of each access analysis object and the corresponding datetime in Universal Time Coordinated (UTC).

Input Arguments

ac — Access analysis

row vector of `Access` objects

Access analysis, specified as a row vector of `Access` objects.

timeIn — Time at which output is calculated

scalar

Time at which the output is calculated, specified as a scalar. If you do not specify a time zone, then the time zone is assumed to be UTC.

Outputs Arguments

s — Access analysis status

scalar or row vector of logical values

Access analysis status, returned as a scalar or row vector of logical values. If `timeIn` is specified, `s` is a row vector, otherwise, the output is a scalar. The status at a given instant is 1 (`true`) if access exists between each pair of adjacent nodes defined by `Sequence`. For example, in a given pair, say defined by `node1` and `node2`, `node1` has access to `node2` and vice versa.

- If a node is a satellite, then the satellite has access to the adjacent node if both nodes are in line of sight of each other.

- If a node is a ground station, then the ground station has access to the adjacent node if the elevation angle of the node with respect to the ground station is greater than or equal to the `MinElevationAngle` property of `GroundStation`.
- If a node is a conical sensor, then the conical sensor has access to the adjacent node if the latter is in the field of view of the former. If the conical sensor is attached to a ground station directly or via a gimbal, then the elevation angle of the adjacent node with respect to the ground station must be greater than or equal to the `MinElevationAngle` property of `GroundStation`.

timeOut — Time samples of output access status

scalar | vector

Time samples of the output access status, returned as a scalar or vector. If the time history of the access status is returned, `timeOut` is a row vector.

See Also

Objects

`satelliteScenario` | `satelliteScenarioViewer`

Functions

`conicalSensor` | `groundStation` | `hide` | `play` | `show`

Topics

“Satellite Scenario Key Concepts” on page 2-61

Introduced in R2021a

aer

Package: satelliteScenario

Calculate azimuth angle, elevation angle, and range in NED frame from another satellite or ground station

Syntax

```
az = aer(objIn,target)
[az,el] = aer(objIn,target)
[az,el,range] = aer(objIn,target)
[az,el,range,timeOut] = aer(objIn,target)
[ ___ ] = aer(objIn,target,timeIn)
```

Description

`az = aer(objIn,target)` returns the history of azimuth angles, between satellite or ground station `objIn` and another satellite or ground station `target` belonging to a given `satelliteScenario` object.

`[az,el] = aer(objIn,target)` returns the history of elevation angles, `el`, between satellite or ground station `objIn` and another satellite or ground station `target`.

`[az,el,range] = aer(objIn,target)` returns the history of the range of `target` with respect to `objIn`.

`[az,el,range,timeOut] = aer(objIn,target)` returns the corresponding time in `timeOut`.

`[___] = aer(objIn,target,timeIn)` returns the outputs at the specified datetime `timeIn`. Specify any output argument combinations from previous syntaxes.

Input Arguments

objIn — First scenario component

Satellite object | GroundStation object

First scenario component, specified as a `Satellite` or `GroundStation` object.

target — Second scenario component

Satellite object | GroundStation object

Second scenario component, specified as a `Satellite` or `GroundStation` object.

timeIn — Time at which output is calculated

scalar | vector | matrix | N-D array

Time at which output is calculated, returned as a scalar, vector, matrix, or N-D array. If no time zone is specified in `timeIn`, the time zone is assumed to be UTC.

Output Arguments

az — Azimuth angles

scalar | vector

Azimuth angles of target in the local azimuth, elevation and range (AER) system, returned as a scalar or vector. Azimuths are measured clockwise from North. Values are specified in degrees in the interval [0, 360). The vector elements correspond to the time samples from the satellite scenario `StartTime` to `StopTime` properties, as specified by the `SampleTime` property. The azimuth angle is defined in the North-East-Down (NED) frame of (and centered at) `objIn` such that 0 degrees is North, 90 degrees is East, 180 degrees is South, and 270 degrees is West.

e1 — Elevation angles

scalar | vector

Elevation angles of target in the local AER system, returned as a scalar or vector. Elevations are measured with respect to a plane that is perpendicular to the normal of the surface of the earth. If `objIn` is on the surface of the Earth, then the plane is tangent to the Earth.

Values are specified in degrees in the closed interval [0 180]. The vector elements correspond to the time samples from the satellite scenario `StartTime` to `StopTime` properties, as specified by the `SampleTime` property. The elevation angle is defined in the NED frame of (and centered at) `objIn` such that 0 deg implies target is on the North East (NE) plane, 90 degrees implies target is directly above `objIn`, and -90 degrees implies target is directly below `objIn`.

range — Distances from local origin

scalar | vector

Distances from the local origin in meters, returned as a scalar or vector.

timeOut — Time samples between start and stop time of scenario

scalar | vector

Time samples corresponding to `az`, `e1`, and `range`, returned as a scalar or vector.

See Also

Objects

`satelliteScenario` | `satelliteScenarioViewer`

Functions

`access` | `conicalSensor` | `groundStation` | `hide` | `play` | `show`

Topics

“Satellite Scenario Key Concepts” on page 2-61

Introduced in R2021a

addBody

Class: Aero.Animation

Package: Aero

Add loaded body to animation object and generate its patches

Syntax

```
idx = addBody(h,b)
idx = h.addBody(b)
```

Description

`idx = addBody(h,b)` and `idx = h.addBody(b)` add a loaded body, `b`, to the animation object `h` and generates its patches. `idx` is the index of the body to be added.

Input Arguments

<code>h</code>	Animation object.
<code>b</code>	Loaded body.

Output Arguments

<code>idx</code>	Index of the body to be added.
------------------	--------------------------------

Examples

Add a second body to the list that is a pointer to the first body. This means that if you change the properties of one body, the properties of the other body change correspondingly.

```
h = Aero.Animation;
idx1 = h.createBody('pa24-250_orange.ac', 'Ac3d');
b = h.Bodies{1};
idx2 = h.addBody(b);
```

addNode (Aero.VirtualRealityAnimation)

Add existing node to current virtual reality world

Syntax

```
addNode(h, node_name, wrl_file)
h.addNode(node_name, wrl_file)
```

Description

`addNode(h, node_name, wrl_file)` and `h.addNode(node_name, wrl_file)` add an existing node, `node_name`, to the current virtual reality world. The `wrl_file` is the file from which the new node is taken. `addNode` adds a new node named `node_name`, which contains (or points to) the `wrl_file`. `node_name` must be unique from other node names in the same `.wrl` file. `wrl_file` must contain the node to be added. You must specify the full path for this file. The `vrnode` object associated with the node object must be defined using a `DEF` statement in the `.wrl` file. This method creates a node object on the world of type `Transform`.

When you use the `addNode` method to add a node, all the objects in the `.wrl` file will be added to the virtual reality animation object under one node. If you want to add separate nodes for the objects in the `.wrl` file, place each node in a separate `.wrl` file.

Examples

Add node to world defined in `chaseHelicopter.wrl`.

```
h = Aero.VirtualRealityAnimation;
h.VRWorldFilename = [matlabroot, '/toolbox/aero/astdemos/asttkoff.wrl'];
copyfile(h.VRWorldFilename, [tempdir, 'asttkoff.wrl'], 'f');
h.VRWorldFilename = [tempdir, 'asttkoff.wrl'];
h.initialize();
h.addNode('Lynx', [matlabroot, '/toolbox/aero/astdemos/chaseHelicopter.wrl']);
```

See Also

[Aero.Node](#) | [Aero.VirtualRealityAnimation](#) | [move](#) | [removeNode](#) | [updateNodes](#)

Introduced in R2007b

addRoute (Aero.VirtualRealityAnimation)

Add VRML ROUTE statement to virtual reality animation

Syntax

```
addRoute(h, nodeOut, eventOut, nodeIn, eventIn)  
h.addRoute(nodeOut, eventOut, nodeIn, eventIn)
```

Description

addRoute(h, nodeOut, eventOut, nodeIn, eventIn) and h.addRoute(nodeOut, eventOut, nodeIn, eventIn) add a VRML ROUTE statement to the virtual reality animation, where nodeOut is the node from which information is routed, eventOut is the event (property), nodeIn is the node to which information is routed, and eventIn is the receiving event (property).

Examples

Add a ROUTE command to connect the Plane position to the Camera1 node.

```
h = Aero.VirtualRealityAnimation;  
h.VRWorldFilename = [matlabroot, '/toolbox/aero/astdemos/asttkoff.wrl'];  
copyfile(h.VRWorldFilename, [tempdir, 'asttkoff.wrl'], 'f');  
h.VRWorldFilename = [tempdir, 'asttkoff.wrl'];  
h.initialize();  
h.addNode('Lynx', [matlabroot, '/toolbox/aero/astdemos/chaseHelicopter.wrl']);  
h.addRoute('Plane', 'translation', 'Camera1', 'translation');
```

See Also

addViewpoint

Introduced in R2007b

addViewpoint (Aero.VirtualRealityAnimation)

Add viewpoint for virtual reality animation

Syntax

```
addViewpoint(h, parent_node, parent_field, node_name)
h.addViewpoint(parent_node, parent_field, node_name)
addViewpoint(h, parent_node, parent_field, node_name, description)
h.addViewpoint(parent_node, parent_field, node_name, description)
addViewpoint(h, parent_node, parent_field, node_name, description, position)
h.addViewpoint(parent_node, parent_field, node_name, description, position)
addViewpoint(h, parent_node, parent_field, node_name, description, position,
orientation)
h.addViewpoint(parent_node, parent_field, node_name, description, position,
orientation)
```

Description

`addViewpoint(h, parent_node, parent_field, node_name)` and `h.addViewpoint(parent_node, parent_field, node_name)` add a viewpoint named `node_name` whose `parent_node` is the parent node field of the `vrnode` object and whose `parent_field` is a valid parent field of the `vrnode` object to the virtual world animation object, `h`.

`addViewpoint(h, parent_node, parent_field, node_name, description)` and `h.addViewpoint(parent_node, parent_field, node_name, description)` add a viewpoint named `node_name` whose `parent_node` is the parent node field of the `vrnode` object and whose `parent_field` is a valid parent field of the `vrnode` object to the virtual world animation object, `h`. `description` is the character vector or string you want to describe the viewpoint.

`addViewpoint(h, parent_node, parent_field, node_name, description, position)` and `h.addViewpoint(parent_node, parent_field, node_name, description, position)` add a viewpoint named `node_name` whose `parent_node` is the parent node field of the `vrnode` object and whose `parent_field` is a valid parent field of the `vrnode` object to the virtual world animation object, `h`. `description` is the character vector or string you want to describe the viewpoint and `position` is the position of the viewpoint. Specify `position` using VRML coordinates (`x y z`).

`addViewpoint(h, parent_node, parent_field, node_name, description, position, orientation)` and `h.addViewpoint(parent_node, parent_field, node_name, description, position, orientation)` add a viewpoint named `node_name` whose `parent_node` is the parent node field of the `vrnode` object and whose `parent_field` is a valid parent field of the `vrnode` object to the virtual world animation object, `h`. `description` is the character vector or string you want to describe the viewpoint, `position` is the position of the viewpoint, and `orientation` is the orientation of the viewpoint. Specify `position` using VRML coordinates (`x y z`). Specify `orientation` in a VRML axes angle format (`x y z Θ`).

Note If you call `addViewpoint` with only the `description` argument, you must set the `position` and `orientation` of the viewpoint with the Simulink 3D Animation `vrnode/setfield` function. This requires you to use VRML coordinates.

Examples

Add a viewpoint named chaseView.

```
h = Aero.VirtualRealityAnimation;  
h.VRWorldFilename = [matlabroot, '/toolbox/aero/astdemos/asttkoff.wrl'];  
copyfile(h.VRWorldFilename, [tempdir, 'asttkoff.wrl'], 'f');  
h.VRWorldFilename = [tempdir, 'asttkoff.wrl'];  
h.initialize();  
h.addViewpoint(h.Nodes{2}.VRNode, 'children', 'chaseView', 'View From Helicopter');
```

See Also

[addRoute](#) | [removeViewpoint](#)

Introduced in R2007b

Aero.Aircraft.ControlState class

Package: Aero

Define control states of fixed-wing state

Description

An object of the Aero.Aircraft.ControlState class defines and manages the control states of fixed-wing states.

Note This class supports fixed-wing objects. Do not directly use this class. To set up the command state vectors on a fixed-wing object, see the `setupControlStates` method.

Class Attributes

Sealed true

For information on class attributes, see “Class Attributes”.

Properties

Position — Current control state value

scalar numeric

Current control state value, specified as a scalar numeric.

Attributes:

GetAccess public
SetAccess public

Data Types: double

MaximumValue — Maximum value of control surface

infinity (default) | scalar numeric

Maximum value of control surface, specified as a scalar numeric.

Attributes:

GetAccess public
SetAccess public

Data Types: double

MinimumValue — Minimum value of control surface

negative infinity (default) | scalar numeric

Minimum value of control surface, specified as a scalar numeric.

Attributes:

GetAccess	public
SetAccess	public

Data Types: double

DependsOn — Control states

["", ""] (default) | two-element vector

Control states upon which the control state depends, specified as a two-element vector.

For asymmetrical control surfaces, the two asymmetrical control states are settable, but the resulting effective control state is not.

Attributes:

GetAccess	public
SetAccess	public

Data Types: char | string

Settable — Current control state value

'on' | 'off'

Current control state value, specified as 'on' or 'off'. Specify 'on' to make the control state settable. Otherwise, set to 'off'.

Tip For asymmetrical control surfaces, the two asymmetrical control states are settable, but the resulting effective control state is not.

Attributes:

GetAccess	public
SetAccess	public

Data Types: double

Properties — Aero.Aircraft.Properties object

scalar

Aero.Aircraft.Properties object, specified as a scalar.

Attributes:

GetAccess	public
SetAccess	public

Examples

Create and Use Fixed-Wing Object

Create and set up dynamic behavior and the current state for the fixed-wing object aircraft.

Create a fixed-wing object.

```
aircraft = Aero.FixedWing()
aircraft =
    FixedWing with properties:
        ReferenceArea: 0
        ReferenceSpan: 0
        ReferenceLength: 0
        Coefficients: [1x1 Aero.FixedWing.Coefficient]
        DegreesOfFreedom: "6DOF"
        Surfaces: [1x0 Aero.FixedWing.Surface]
        Thrusts: [1x0 Aero.FixedWing.Thrust]
        AspectRatio: NaN
        UnitSystem: "Metric"
        AngleSystem: "Radians"
        TemperatureSystem: "Kelvin"
        Properties: [1x1 Aero.Aircraft.Properties]
```

To define the aircraft dynamic behavior, set a coefficient for it.

```
aircraft = setCoefficient(aircraft, "CD", "Zero", 0.27)
aircraft =
    FixedWing with properties:
        ReferenceArea: 0
        ReferenceSpan: 0
        ReferenceLength: 0
        Coefficients: [1x1 Aero.FixedWing.Coefficient]
        DegreesOfFreedom: "6DOF"
        Surfaces: [1x0 Aero.FixedWing.Surface]
        Thrusts: [1x0 Aero.FixedWing.Thrust]
        AspectRatio: NaN
        UnitSystem: "Metric"
        AngleSystem: "Radians"
        TemperatureSystem: "Kelvin"
        Properties: [1x1 Aero.Aircraft.Properties]
```

Define the aircraft's current state.

```
state = Aero.FixedWing.State("Mass", 500)
state =
    State with properties:
        Alpha: 0
        Beta: 0
        AlphaDot: 0
        BetaDot: 0
        Mass: 500
```



```

        Inertia: [3×3 table]
    CenterOfGravity: [0 0 0]
    CenterOfPressure: [0 0 0]
        AltitudeMSL: 0
    GroundHeight: 0
        XN: 0
        XE: 0
        XD: 0
        U: 50
        V: 0
        W: 0
        Phi: 0
    Theta: 0
    Psi: 0
        P: 0
        Q: 0
        R: 0
    Weight: 4905
    AltitudeAGL: 0
    Airspeed: 50
    GroundSpeed: 50
    MachNumber: 0.1469
    BodyVelocity: [50 0 0]
    GroundVelocity: [50 0 0]
        Ur: 50
        Vr: 0
        Wr: 0
    FlightPathAngle: 0
    CourseAngle: 0
    InertialToBodyMatrix: [3×3 double]
    BodyToInertialMatrix: [3×3 double]
    BodyToWindMatrix: [3×3 double]
    WindToBodyMatrix: [3×3 double]
    DynamicPressure: 1.5312e+03
    Environment: [1×1 Aero.Aircraft.Environment]
    UnitSystem: "Metric"
    AngleSystem: "Radians"
    TemperatureSystem: "Kelvin"
    ControlStates: [1×0 Aero.Aircraft.ControlState]
    OutOfRangeAction: "Limit"
    DiagnosticAction: "Warning"
    Properties: [1×1 Aero.Aircraft.Properties]

```

Calculate the forces and moments on the aircraft.

`[F, M] = forcesAndMoments(aircraft, state)`

F =

```

    0
    0
    4905

```

M =

```

    0

```

0
0

Limitations

You cannot subclass `Aero.Aircraft.ControlState`.

See Also

`Aero.FixedWing` | `Aero.FixedWing.State` | `setupControlStates`

Topics

“Determine Nonlinear Dynamics and Static Stability of Fixed-Wing Aircraft” on page 5-128

“Perform Controls and Static Stability Analysis with Linearized Fixed-Wing Aircraft” on page 5-115

Introduced in R2021a

Aero.Aircraft.Environment class

Package: Aero

Properties defining and managing aircraft environment

Description

An object of the Aero.Aircraft.Environment class defines and manages aircraft environments.

Class Attributes

Sealed true

For information on class attributes, see “Class Attributes”.

Creation

Description

`aeroAircraftEnvironment = Aero.Aircraft.Environment` creates a single Aero.Aircraft.Environment object with default property values.

`aeroAircraftEnvironment = Aero.Aircraft.Environment(N)` creates an N -by- N matrix of Aero.Aircraft.Environment objects with default property values.

`aeroAircraftEnvironment = Aero.Aircraft.Environment(M,N,P,...)` or `Aero.Aircraft.Environment([M N P ...])` creates an M -by- N -by- P -by-... array of Aero.Aircraft.Environment objects with default property values.

`aeroAircraftEnvironment = Aero.Aircraft.Environment(size(A))` creates an Aero.Aircraft.Environment object that is the same size as A and all Aero.Aircraft.Environment objects.

`aeroAircraftEnvironment = Aero.Aircraft.Environment(__,property,propertyValue)` creates an array of Aero.Aircraft.Environment objects with *property*, *propertyValue* pairs applied to each of the Aero.Aircraft.Environment array objects. For a list of properties, see “Properties” on page 4-28.

Input Arguments

N — Number of aircraft objects

scalar

Number of aircraft objects, specified as a scalar.

M — Number of aircraft objects

scalar

Number of aircraft objects, specified as a scalar.

Attributes:

GetAccess public
SetAccess public

Data Types: double

Pressure – Static air pressure

101325 (default) | scalar numeric

Static air pressure, specified as a scalar numeric in these units:

Unit	Unit System
Pascals (Pa)	'Metric'
Pounds per foot ² (psf)	'English (kts)' and 'English (ft/s)'

Attributes:

GetAccess public
SetAccess public

Data Types: double

SpeedOfSound – Speed of sound

340.2941 (default) | scalar numeric

Speed of sound, specified as a scalar numeric in these units:

Unit	Unit System
Meters per second (m/s)	'Metric'
Feet per second (ft/s)	'English (kts)'
Knots (kts)	'English (ft/s)'

Attributes:

GetAccess public
SetAccess public

Data Types: double

Gravity – Acceleration due to gravity

9.81 (default) | scalar numeric

Acceleration due to gravity, specified as a scalar numeric in these units:

Unit	Unit System
Meters per second ² (m/s ²)	'Metric'
Feet per second ^s (ft/s ²)	'English (kts)' and 'English (ft/s)'

Attributes:

GetAccess	public
SetAccess	public

Data Types: double

Properties — Aero.Aircraft.Properties object

scalar

Aero.Aircraft.Properties object, specified as a scalar.

Attributes:

GetAccess	public
SetAccess	public

Examples**Create Aero.Aircraft.Environment Object**

Create an Aero.Aircraft.Environment object.

Create an Aero.Aircraft.Environment object.

```
env = Aero.Aircraft.Environment('Gravity', 32.2)
```

```
env =
```

Environment with properties:

```
WindVelocity: [0 0 0]  
Density: 1.2250  
Temperature: 288.1500  
Pressure: 101352  
SpeedOfSound: 340.2941  
Gravity: 32.2000  
Properties: [1x1 Aero.Aircraft.Properties]
```

Limitations

You cannot subclass Aero.Aircraft.Environment.

See Also

Aero.FixedWing | setupControlStates

Topics

“Determine Nonlinear Dynamics and Static Stability of Fixed-Wing Aircraft” on page 5-128

“Perform Controls and Static Stability Analysis with Linearized Fixed-Wing Aircraft” on page 5-115

Introduced in R2021a

Aero.Aircraft.Properties class

Package: Aero

Properties defining and managing aircraft

Description

An object of the `Aero.Aircraft.Properties` class defines and manages aircraft components. Use this object to model and analyze an aircraft. The object contains the static data for the aircraft, such as reference values, coefficients, and deflection angles.

Class Attributes

Sealed true

For information on class attributes, see “Class Attributes”.

Creation

Description

`aeroAircraft = Aero.Aircraft.Properties` creates a single `Aero.Aircraft.Properties` object with default property values.

`aeroAircraft = Aero.Aircraft.Properties(N)` creates an N -by- N matrix of `Aero.Aircraft.Properties` objects with default property values.

`aeroAircraft = Aero.Aircraft.Properties(M,N,P,...)` or `Aero.Aircraft.Properties([M N P ...])` creates an M -by- N -by- P -by-... array of `Aero.Aircraft.Properties` objects with default property values.

`aeroAircraft = Aero.Aircraft.Properties(size(A))` creates an `Aero.Aircraft.Properties` object that is the same size as `A` and all `Aero.Aircraft.Properties` objects.

`aeroAircraft = Aero.Aircraft.Properties(__,property,propertyValue)` creates an array of `Aero.Aircraft.Properties` objects with *property*, *propertyValue* pairs applied to each of the `Aero.Aircraft.Properties` array objects. For a list of properties, see “Properties” on page 4-32.

Input Arguments

N — Number of aircraft objects

scalar

Number of aircraft objects, specified as a scalar.

M — Number of aircraft objects

scalar

Number of aircraft objects, specified as a scalar.

P — Number of aircraft objects

scalar

Number of aircraft objects, specified as a scalar.

A — Size of aircraft object

scalar

Size of aircraft object, specified as a scalar.

Properties

Name — Object name

scalar

Object name, specified as a scalar string or character vector. The update method of an `Aero.FixedWing.*` object uses this name to update the `Simulink.LookupTable.StructTypeInfo.Name` property.

Attributes:

GetAccess	public
SetAccess	public

Data Types: char | string

Description — Object description

string array

Object description, specified as a scalar string or character vector.

Attributes:

GetAccess	public
SetAccess	public

Data Types: char | string

Type — Object type

scalar string

Object type, specified as a scalar string or character vector.

Attributes:

GetAccess	public
SetAccess	public

Data Types: char | string

Version — Object version

scalar string

Object version, specified as a scalar string or character vector.

Attributes:

GetAccess	public
SetAccess	public

Data Types: char | string

Examples**Create Aero.Aircraft.Properties Object**

Create an Aero.Aircraft.Properties object and set object name to MyAircraft.

Create a fixed-wing object.

```
props = Aero.Aircraft.Properties('Name', 'MyAircraft')
```

```
props =
```

```
Properties with properties:
```

```
    Name: "MyAircraft"
Description: ""
    Type: ""
    Version: ""
```

Limitations

- This class requires a Simulink license.
- You cannot subclass Aero.Aircraft.Properties.

See Also

Aero.FixedWing

Topics

“Determine Nonlinear Dynamics and Static Stability of Fixed-Wing Aircraft” on page 5-128

Introduced in R2021a

Aero.Animation class

Package: Aero

Visualize aerospace animation

Description

Use the Aero.Animation class to visualize flight data without any other tool or toolbox. You only need the Aerospace Toolbox to visualize this data.

Construction

Aero.Animation Construct animation object

Methods

addBody	Add loaded body to animation object and generate its patches
createBody	Create body and its associated patches in animation
delete	Destroy animation object
hide	Hide animation figure
initialize	Create animation object figure and axes and build patches for bodies
initIfNeeded	Initialize animation graphics if needed
moveBody	Move body in animation object
play	Animate Aero.Animation object given position/angle time series
removeBody	Remove one body from animation
show	Show animation object figure
updateBodies	Update bodies of animation object
updateCamera	Update camera in animation object

Properties

Bodies	Specify name of animation object
Camera	Specify camera that animation object contains
Figure	Specify name of figure object
FigureCustomizationFcn	Specify figure customization function
FramesPerSecond	Animation rate
Name	Specify name of animation object
TCurrent	Current time
TFinal	End time
TimeScaling	Scaling time
TStart	Start time
VideoCompression	Video recording compression file type
VideoFileName	Video recording file name
VideoQuality	Video recording quality
VideoRecord	Video recording
VideoTFinal	Video recording stop time for scheduled recording
VideoTStart	Video recording start time for scheduled recording

See Also

[Aero.FlightGearAnimation](#) | [Aero.VirtualRealityAnimation](#)

Topics

“Aero.Animation Objects” on page 2-19

Aero.Animation

Class: Aero.Animation

Package: Aero

Construct animation object

Syntax

```
h = Aero.Animation
```

Description

`h = Aero.Animation` constructs an animation object. The animation object is returned to `h`.

Note The `Aero.Animation` constructor does not retain the properties of previously created animation objects, even those that you have saved to a MAT-file. This means that subsequent calls to the animation object constructor always create animation objects with default properties.

Examples

```
h=Aero.Animation
```

Aero.Body

Create body object for use with animation object

Syntax

`h = Aero.Body`

Description

`h = Aero.Body` constructs a body for an animation object. The animation object is returned in `h`. To use the `Aero.Body` object, you typically:

- 1 Create the animation body.
- 2 Configure or customize the body object.
- 3 Load the body.
- 4 Generate patches for the body (requires an axes from a figure).
- 5 Set time series data source.
- 6 Move or update the body.

By default, an `Aero.Body` object natively uses aircraft x - y - z coordinates for the body geometry and the time series data. It expects the rotation order z - y - x (psi, theta, phi).

Convert time series data from other coordinate systems on the fly by registering a different `CoordTransformFcn` function.

Constructor Summary

Constructor	Description
Body	Construct body object for use with animation object.

Method Summary

Method	Description
<code>findstartstoptimes</code>	Return start and stop times of time series data.
<code>generatePatches</code>	Generate patches for body with loaded face, vertex, and color data.
<code>load</code>	Get geometry data from source.
<code>move</code>	Change <code>Aero.Body</code> position and orientation.
<code>update</code>	Changes body position and orientation versus time data.

Property Summary

Property	Description	Values
CoordTransformFcn	Specify a function that controls the coordinate transformation.	Character vector string
Name	Specify name of body.	
Position	Specify position of body.	MATLAB array
Rotation	Specify rotation of body.	MATLAB array
Geometry	Specify geometry of body.	handle
PatchGenerationFcn	Specify patch generation function.	MATLAB array
PatchHandles	Specify patch handles.	MATLAB array
ViewingTransform	Specify viewing transform.	MATLAB array
TimeseriesSource	Specify time series source.	MATLAB array
TimeseriesSourceType	Specify the type of time series data stored in 'TimeseriesSource'. Five values are available. They are listed in TimeseriesSourceType Properties. The default value is 'Array6DoF'.	Character vector string
TimeseriesReadFcn	Specify time series read function.	MATLAB array

The time series data, stored in the property 'TimeseriesSource', is interpreted according to the 'TimeseriesSourceType' property, which can be one of:

TimeseriesSourceType Properties

Property	Description
'Timeseries'	MATLAB time series data with six values per time: x y z phi theta psi The values are resampled.
'StructureWithTime'	Simulink struct with time (for example, Simulink root outport logging 'Structure with time'): <ul style="list-style-type: none"> • signals(1).values: x y z • signals(2).values: phi theta psi Signals are linearly interpolated vs. time using interp1.
'Array6DoF'	A double-precision array in n rows and 7 columns for 6-DoF data: time x y z phi theta psi. If a double-precision array of 8 or more columns is in 'TimeseriesSource', the first 7 columns are used as 6-DoF data.
'Array3DoF'	A double-precision array in n rows and 4 columns for 3-DoF data: time x z theta. If a double-precision array of 5 or more columns is in 'TimeseriesSource', the first 4 columns are used as 3-DoF data.
'Custom'	Position and angle data is retrieved from 'TimeseriesSource' by the currently registered 'TimeseriesReadFcn'.

See Also

Aero.Geometry

Introduced in R2007a

Aero.Camera

Construct camera object for use with animation object

Syntax

```
h = Aero.Camera
```

Description

`h = Aero.Camera` constructs a camera object `h` for use with an animation object. The camera object uses the registered coordinate transform. By default, this is an aerospace body coordinate system. Axes of custom coordinate systems must be orthogonal.

By default, an `Aero.Body` object natively uses aircraft x - y - z coordinates for the body geometry and the time series data. Convert time series data from other coordinate systems on the fly by registering a different `CoordTransformFcn` function.

For more information, see:

- “Overlaying Simulated and Actual Flight Data” on page 5-30
- “Camera Graphics Terminology”
- “Low-Level Camera Properties”

Constructor Summary

Constructor	Description
Camera	Construct camera object for use with animation object.

Method Summary

Method	Description
update	Update camera position based on time and position of other <code>Aero.Body</code> objects.

Property Summary

Property	Description	Values
<code>CoordTransformFcn</code>	Specify a function that controls the coordinate transformation.	MATLAB array
<code>PositionFcn</code>	Specify a function that controls the position of a camera relative to an animation body.	MATLAB array
<code>Position</code>	Specify position of camera.	MATLAB array [-150, -50, 0]
<code>Offset</code>	Specify offset of camera.	MATLAB array [-150, -50, 0]

Property	Description	Values
AimPoint	Specify aim point of camera.	MATLAB array [0,0,0]
UpVector	Specify up vector of camera.	MATLAB array [0,0,-1]
ViewAngle	Specify view angle of camera.	MATLAB array {3}
ViewExtent	Specify view extent of camera.	MATLAB array {[-50,50]}
xlim	Specify x-axis limit of camera.	MATLAB array {[-50,50]}
ylim	Specify y-axis limit of camera.	MATLAB array {[-50,50]}
zlim	Specify z-axis limit of camera.	MATLAB array {[-50,50]}
PrevTime	Specify previous time of camera.	MATLAB array {0}
UserData	Specify custom data.	MATLAB array {[]}

See Also

Aero.Geometry

Introduced in R2007a

aeroDataPackage

Start Add-On Explorer to download, install, or uninstall aerospace-specific data

Syntax

aeroDataPackage

Description

aeroDataPackage opens Add-On Explorer. To see a list of available data, run Add-On Explorer and select the data you want.

Examples

Start Add-On Explorer

Start Add-On Explorer to add data.

aeroDataPackage

The Add-On Explorer starts. Follow the instructions to download your data.

Limitations

The aeroDataPackage function is not available for Aerospace Toolbox Online.

See Also

Topics

“Add Ephemeris and Geoid Data for Aerospace Products” on page 3-2

Introduced in R2014a

Aero.FixedWing class

Package: Aero

Define fixed-wing aircraft

Description

An object of the Aero.FixedWing class defines a fixed-wing aircraft. Use this object to model and analyze a fixed-wing aircraft. It contains the static data for the aircraft, such as reference values, coefficients, and deflection angles.

To perform static analysis of fixed-wing aircraft, use this object in conjunction with the Aero.FixedWing.State object. The Aero.FixedWing.State object contains the aircraft information at a particular aircraft state.

For more information on fixed-wing aircraft definitions, see “More About” on page 4-50.

Class Attributes

Sealed true

For information on class attributes, see “Class Attributes”.

Creation

Description

`fixedWing = Aero.FixedWing` creates a single Aero.FixedWing object with default property values.

`fixedWing = Aero.FixedWing(N)` creates an N -by- N matrix of Aero.FixedWing objects with default property values.

`fixedWing = Aero.FixedWing(M,N,P,...)` or `Aero.FixedWing([M N P ...])` create an M -by- N -by- P -by-... array of Aero.FixedWing objects with default property values.

`fixedWing = Aero.FixedWing(size(A))` creates an Aero.FixedWing object that is the same size as A and all Aero.FixedWing objects.

`fixedWing = Aero.FixedWing(__,property,propertyValue)` creates an array of Aero.FixedWing objects with *property*, *propertyValue* pairs applied to each of the Aero.FixedWing array objects. For a list of properties, see “Properties” on page 4-44.

Input Arguments

N — Number of fixed-wing objects

scalar

Number of fixed-wing objects, specified as a scalar.

M — Number of fixed-wing objects

scalar

Number of fixed-wing objects, specified as a scalar.

P — Number of fixed-wing objects

scalar

Number of fixed-wing objects, specified as a scalar.

A — Size of fixed-wing object

scalar

Size of fixed-wing object, specified as a scalar.

Properties

Public Properties

UnitSystem — Unit system

'Metric' (default) | 'English (kts)' | 'English (ft/s)' | scalar string | character vector

Unit system, specified as a scalar string or character vector.

Attributes:

GetAccess	public
SetAccess	public

Data Types: string | char

AngleSystem — Angle system

'Radians' (default) | 'Degrees'

Angle system, specified as 'Radians' or 'Degrees'.

Attributes:

GetAccess	public
SetAccess	public

Data Types: string | char

TemperatureSystem — Temperature system

'Kelvin' (default) | 'Celsius' | 'Rankine' | 'Fahrenheit'

Temperature system, specified as 'Kelvin', 'Celsius', 'Rankine', or 'Fahrenheit'.

Attributes:

GetAccess	public
SetAccess	public

Data Types: string | char

ReferenceArea — Reference area

0 (default) | scalar numeric

Attributes:

GetAccess public
SetAccess public

Data Types: double

DegreesOfFreedom — Degrees of freedom

'6DOF' (default) | '3DOF' | 'PM4' | 'PM6'

Degrees of freedom, specified as a string or character vector.

Degrees of Freedom	Description
'6DOF'	Six degrees of freedom. Describes translational and rotational movement in 3-D space.
'3DOF'	Three degrees of freedom. Describes translational and rotational movement in 2-D space.
'PM4'	Fourth order point-mass. Describes translational movement in 2-D space.
'PM6'	Sixth order point-mass. Describes translational movement in 3-D space.

Attributes:

GetAccess public
SetAccess public

Data Types: string | char

Surfaces — Aero.FixedWing.Surface definitions

vector

Aero.FixedWing.Surface definitions, specified as a vector that contains the definitions of the surfaces on the fixed-wing aircraft. The object ignores this property if no value is set.

Attributes:

GetAccess public
SetAccess public

Data Types: double

Thrusts — Aero.FixedWing.Thrust definitions

vector

Aero.FixedWing.Thrust definitions, specified as a vector that contains the definitions of the thrust on the fixed-wing aircraft. The object ignores this property if no value is set.

Attributes:

GetAccess	public
SetAccess	public

Data Types:

Protected Properties**AspectRatio – Aspect ratio**

scalar numeric

Aspect ratio, specified as a scalar numeric, commonly denoted as 'AR'. This value depends on the values of ReferencedArea and ReferenceSpan, with this equation:

$$\text{AspectRatio} = \text{ReferenceSpan}^2 / \text{ReferencedArea}$$

The object ignores this property if no value is set.

Attributes:

GetAccess	Restricts access
SetAccess	protected

Data Types: double

Methods**Public Methods**

criteriaTable	Construct criteria table for fixed-wing static stability analysis
datcomToFixedWing	Construct fixed-wing aircraft from Digital DATCOM structure
forcesAndMoments	Calculate forces and moments of fixed-wing aircraft
getCoefficient	Get coefficient value for Aero.FixedWing object
getControlStates	Get control states for Aero.FixedWing object
linearize	Return linear state-space model
nonlinearDynamics	Calculate dynamics of fixed-wing aircraft
setCoefficient	Set coefficient value for Aero.FixedWing object
staticStability	Calculate static stability of fixed-wing aircraft
update	Update Aero.FixedWing object

Examples**Create and Use Fixed-Wing Object**

Create and set up dynamic behavior and the current state for the fixed-wing object aircraft.

Create a fixed-wing object.

```
aircraft = Aero.FixedWing()
```

```
aircraft =
```

```
    FixedWing with properties:
```

```

    ReferenceArea: 0
    ReferenceSpan: 0
    ReferenceLength: 0
    Coefficients: [1x1 Aero.FixedWing.Coefficient]
    DegreesOfFreedom: "6DOF"
        Surfaces: [1x0 Aero.FixedWing.Surface]
        Thrusts: [1x0 Aero.FixedWing.Thrust]
    AspectRatio: NaN
    UnitSystem: "Metric"
    AngleSystem: "Radians"
    TemperatureSystem: "Kelvin"
    Properties: [1x1 Aero.Aircraft.Properties]

```

To define the aircraft dynamic behavior, set a coefficient for it.

```
aircraft = setCoefficient(aircraft, "CD", "Zero", 0.27)
```

```
aircraft =
```

FixedWing with properties:

```

    ReferenceArea: 0
    ReferenceSpan: 0
    ReferenceLength: 0
    Coefficients: [1x1 Aero.FixedWing.Coefficient]
    DegreesOfFreedom: "6DOF"
        Surfaces: [1x0 Aero.FixedWing.Surface]
        Thrusts: [1x0 Aero.FixedWing.Thrust]
    AspectRatio: NaN
    UnitSystem: "Metric"
    AngleSystem: "Radians"
    TemperatureSystem: "Kelvin"
    Properties: [1x1 Aero.Aircraft.Properties]

```

Define the aircraft's current state.

```
state = Aero.FixedWing.State("Mass", 500)
```

```
state =
```

State with properties:

```

    Alpha: 0
    Beta: 0
    AlphaDot: 0
    BetaDot: 0
    Mass: 500
    Inertia: [3x3 table]
    CenterOfGravity: [0 0 0]
    CenterOfPressure: [0 0 0]
    AltitudeMSL: 0
    GroundHeight: 0
    XN: 0
    XE: 0
    XD: 0
    U: 50
    V: 0
    W: 0
    Phi: 0

```



```

        Theta: 0
        Psi: 0
        P: 0
        Q: 0
        R: 0
        Weight: 4905
        AltitudeAGL: 0
        Airspeed: 50
        GroundSpeed: 50
        MachNumber: 0.1469
        BodyVelocity: [50 0 0]
        GroundVelocity: [50 0 0]
        Ur: 50
        Vr: 0
        Wr: 0
        FlightPathAngle: 0
        CourseAngle: 0
        InertialToBodyMatrix: [3×3 double]
        BodyToInertialMatrix: [3×3 double]
        BodyToWindMatrix: [3×3 double]
        WindToBodyMatrix: [3×3 double]
        DynamicPressure: 1.5312e+03
        Environment: [1×1 Aero.Aircraft.Environment]
        UnitSystem: "Metric"
        AngleSystem: "Radians"
        TemperatureSystem: "Kelvin"
        ControlStates: [1×0 Aero.Aircraft.ControlState]
        OutOfRangeAction: "Limit"
        DiagnosticAction: "Warning"
        Properties: [1×1 Aero.Aircraft.Properties]

```

Calculate the forces and moments on the aircraft.

```
[F, M] = forcesAndMoments(aircraft, state)
```

F =

```

    0
    0
  4905

```

M =

```

    0
    0
    0

```

Limitations

You cannot subclass `Aero.FixedWing`.

More About

Fixed-Wing Definitions

The `FixedWing` object holds the main definition of a fixed-wing aircraft. The object has a main set of body coefficients defined by these tables:

Body Coefficients in Wind Frame

Body Coefficients	Wind Frame								
	Zero	U	Alpha	AlphaRate	Theta	Beta	BetaRate	Phi	Psi
CD									
CY									
CL									
CI									
Cm									
Cn									

Body Coefficients in Body Frame

Body Coefficients	Wind Frame								
	Zero	U	Alpha	AlphaRate	Theta	Beta	BetaRate	Phi	Psi
CX									
CY									
CZ									
CI									
Cm									
Cn									

See Also

`Aero.FixedWing.Coefficient` | `Aero.FixedWing.State` | `Aero.FixedWing.Surface` | `Aero.FixedWing.Thrust` | `Simulink.LookupTable` | `getCoefficient` | `setCoefficient`

Topics

“Determine Nonlinear Dynamics and Static Stability of Fixed-Wing Aircraft” on page 5-128

“Perform Controls and Static Stability Analysis with Linearized Fixed-Wing Aircraft” on page 5-115

“Customize Fixed-Wing Aircraft with Additional Aircraft States” on page 5-122

Introduced in R2021a

Aero.FixedWing.Coefficient class

Package: Aero

Create Aero.FixedWing aircraft coefficient set

Description

Aero.FixedWing.Coefficient creates an Aero.FixedWing coefficient set that describes the behavior and body of an aircraft.

Class Attributes

Sealed true

For information on class attributes, see “Class Attributes”.

Creation

Description

`fixedWingCoefficient = Aero.FixedWing.Coefficient` creates a single Aero.FixedWing.Coefficient object with default property values.

`fixedWingCoefficient = Aero.FixedWing.Coefficient(N)` creates an N -by- N matrix of Aero.FixedWing.Coefficient objects with default property values.

`fixedWingCoefficient = Aero.FixedWing.Coefficient(M,N,P,...)` or `Aero.FixedWing.Coefficient([M N P ...])` creates an M -by- N -by- P -by-... array of Aero.FixedWing.Coefficient objects with default property values.

`fixedWingCoefficient = Aero.FixedWing.Coefficient(size(A))` creates an Aero.FixedWing.Coefficient object that is the same size as A and all Aero.FixedWing.Coefficient objects.

`fixedWingCoefficient = Aero.FixedWing.Coefficient(__,property,propertyValue)` creates an array of Aero.FixedWing.Coefficient objects with *property*, *propertyValue* pairs applied to each of the Aero.FixedWing.Coefficient array objects. For a list of properties, see “Properties” on page 4-52.

Input Arguments

N — Number of fixed-wing coefficient objects

scalar

Number of fixed-wing coefficient objects, specified as a scalar.

M — Number of fixed-wing coefficient objects

scalar

Number of fixed-wing coefficient objects, specified as a scalar.

P — Number of fixed-wing coefficient objects

scalar

Number of fixed-wing coefficient objects, specified as a scalar.

A — Size of fixed-wing coefficient object

scalar

Size of fixed-wing coefficient object, specified as a scalar.

Properties**Public Properties****Table — Coefficient values**6-by-*N* table

Coefficient values, specified in a 6-by-*N* table. Each row in the table must be a member of and in the same order as the “StateOutput” on page 4-0 property.

Setting the Table property also sets the contents of the Values property and StateVariables to the Table property variables. To have a Simulink.LookupTable object and a constant value in the same column, use the setCoefficient or set the desired content of the Values property. Setting the Table property does not set the ReferenceFrame.

Note Tables must have a single data type per column. If there are both constant values and Simulink.LookupTable objects in a given column, the Table property automatically converts the constants to Simulink.LookupTable objects.

Attributes:

GetAccess	public
SetAccess	public

Data Types: double

Values — Coefficient values6-by-*N* cell array

Coefficient values, specified as a 6-by-*N* cell array. Each entry in the cell array must be a single coefficient value corresponding to the StateOutput (row) and StateVariable (column) properties. Each coefficient value must be a scalar numeric value or a Simulink.LookupTable object. If a value is a Simulink.LookupTable object, the FieldName of each breakpoint must be a valid property of the Aero.FixedWing.State object.

Unlike the Table property, Values do need to be a single data type per column.

Attributes:

GetAccess	public
SetAccess	public

Data Types: double

StateVariables — State variable names1-by-*N* vector

State variable names, specified as a 1-by-*N* vector of strings. Each entry in this property corresponds to a column in the `Values` property. Each entry in `StateVariables` must be a valid property in the `Aero.FixedWing.State` object. Adding a state variable adds a column of zeros to the end of the `Values` cell array.

Attributes:

GetAccess	public
SetAccess	public

Data Types: char | string

ReferenceFrame — Reference frame for coefficients

Wind (default) | Body

Reference frame for coefficients, specified as Wind or Body with these outputs:

Reference Frame	Coefficient Output
Wind	Forces:
	Moments:
Body	Forces:
	Moments:

Example of Wind table:

Coefficient	State
CD	<i>state</i>
CY	<i>state</i>
CL	<i>state</i>
Cl	<i>state</i>
Cm	<i>state</i>
Cn	<i>state</i>

Example of Body table:

Coefficient	State
CX	<i>state</i>
CY	<i>state</i>
CZ	<i>state</i>
Cl	<i>state</i>
Cm	<i>state</i>

Wind	Body
CY	CY
CL	CZ
Cl	Cl
Cm	Cm
Cn	Cn

This property depends on ReferenceFrame.

Attributes:

GetAccess Restricts access
SetAccess protected

Data Types: char | string

Methods

Public Methods

getCoefficient Get coefficient values from fixed-wing coefficient object
setCoefficient Set coefficient values for fixed-wing coefficient object
update Update Aero.FixedWing.Coefficient object

Examples

Create and Use Fixed-Wing Object

Create and set up dynamic behavior and the current state for the fixed-wing object aircraft.

Create a fixed-wing object.

```
aircraft = Aero.FixedWing()
```

```
aircraft =
```

```
FixedWing with properties:
```

```
ReferenceArea: 0
ReferenceSpan: 0
ReferenceLength: 0
Coefficients: [1x1 Aero.FixedWing.Coefficient]
DegreesOfFreedom: "6DOF"
Surfaces: [1x0 Aero.FixedWing.Surface]
Thrusts: [1x0 Aero.FixedWing.Thrust]
AspectRatio: NaN
UnitSystem: "Metric"
AngleSystem: "Radians"
TemperatureSystem: "Kelvin"
Properties: [1x1 Aero.Aircraft.Properties]
```

To define the aircraft dynamic behavior, set a coefficient for it.

```
aircraft = setCoefficient(aircraft, "CD", "Zero", 0.27)
```

```
aircraft =
```

```
FixedWing with properties:
```

```
ReferenceArea: 0
ReferenceSpan: 0
ReferenceLength: 0
Coefficients: [1x1 Aero.FixedWing.Coefficient]
DegreesOfFreedom: "6DOF"
Surfaces: [1x0 Aero.FixedWing.Surface]
Thrusts: [1x0 Aero.FixedWing.Thrust]
AspectRatio: NaN
UnitSystem: "Metric"
AngleSystem: "Radians"
TemperatureSystem: "Kelvin"
Properties: [1x1 Aero.Aircraft.Properties]
```

Define the aircraft's current state.

```
state = Aero.FixedWing.State("Mass", 500)
```

```
state =
```

```
State with properties:
```

```
Alpha: 0
Beta: 0
AlphaDot: 0
BetaDot: 0
Mass: 500
Inertia: [3x3 table]
CenterOfGravity: [0 0 0]
CenterOfPressure: [0 0 0]
AltitudeMSL: 0
GroundHeight: 0
XN: 0
XE: 0
XD: 0
U: 50
V: 0
W: 0
Phi: 0
Theta: 0
Psi: 0
P: 0
Q: 0
R: 0
Weight: 4905
AltitudeAGL: 0
Airspeed: 50
GroundSpeed: 50
MachNumber: 0.1469
BodyVelocity: [50 0 0]
GroundVelocity: [50 0 0]
Ur: 50
Vr: 0
```



```

        Wr: 0
    FlightPathAngle: 0
    CourseAngle: 0
    InertialToBodyMatrix: [3x3 double]
    BodyToInertialMatrix: [3x3 double]
    BodyToWindMatrix: [3x3 double]
    WindToBodyMatrix: [3x3 double]
    DynamicPressure: 1.5312e+03
    Environment: [1x1 Aero.Aircraft.Environment]
    UnitSystem: "Metric"
    AngleSystem: "Radians"
    TemperatureSystem: "Kelvin"
    ControlStates: [1x0 Aero.Aircraft.ControlState]
    OutOfRangeAction: "Limit"
    DiagnosticAction: "Warning"
    Properties: [1x1 Aero.Aircraft.Properties]

```

Calculate the forces and moments on the aircraft.

```
[F, M] = forcesAndMoments(aircraft, state)
```

F =

```

    0
    0
 4905

```

M =

```

    0
    0
    0

```

Limitations

- This class requires a Simulink license if the coefficient table contains `Simulink.LookupTable` objects.
- You cannot subclass `Aero.FixedWing.Coefficient`.

See Also

`Aero.FixedWing` | `Aero.FixedWing.Surface` | `Aero.FixedWing.Thrust` | `Simulink.LookupTable` | `setCoefficient`

Introduced in R2021a

Aero.FixedWing.State class

Package: Aero

Define condition of Aero.FixedWing aircraft at time instant

Description

Use the Aero.FixedWing.State class to define the condition of an Aero.FixedWing aircraft at a time instant. The Aero.FixedWing.State object contains the information about the current state of an aircraft at a single instance in time. A subclass can inherit the Aero.FixedWing.State.

- To get dependent properties defined by subclass, use the `getState` method.
- To set dependent properties, use the `setState` method.
- To use custom state properties within the Aero.FixedWing object methods, create a subclass.

Class Attributes

Sealed false

For information on class attributes, see “Class Attributes”.

Creation

Description

Aero.FixedWing.State creates a single Aero.FixedWing.State object with default property values..

Aero.FixedWing.State(N) creates an N -by- N matrix of Aero.FixedWing.State.

Aero.FixedWing.State(M,N,P,...) or Aero.FixedWing.State([M N P ...]) creates an M -by- N -by- P -by-... array of Aero.FixedWing.State.

Aero.FixedWing.State(size(A)) creates an Aero.FixedWing.State object that is the same size as A and all Aero.FixedWing.State objects.

Aero.FixedWing.State(__,property,propertyValue) creates an array of Aero.FixedWing.State objects with *property*, *propertyValue* pairs applied to each of the Aero.FixedWing array objects. For a list of properties, see “Properties” on page 4-59.

Input Arguments

N — Number of fixed-wing objects

scalar

Number of fixed-wing objects, specified as a scalar.

M — Number of fixed-wing objects

scalar

Number of fixed-wing objects, specified as a scalar.

P — Number of fixed-wing objects

scalar

Number of fixed-wing objects, specified as a scalar.

A — Size of fixed-wing object

scalar

Size of fixed-wing object, specified as a scalar.

Properties

Public Properties

UnitSystem — Unit system

'Metric' (default) | 'English (kts)' | 'English (ft/s)' | scalar string | character vector

Unit system, specified as a scalar string or character vector.

Attributes:

GetAccess	public
SetAccess	public

Data Types: string | char

AngleSystem — Angle system

'Radians' (default) | 'Degrees'

Angle system, specified as 'Radians' or 'Degrees'.

Attributes:

GetAccess	public
SetAccess	public

Data Types: string | char

TemperatureSystem — Temperature system

'Kelvin' (default) | 'Celsius' | 'Rankine' | 'Fahrenheit'

Temperature system, specified as 'Kelvin', 'Celsius', 'Rankine', or 'Fahrenheit'.

Attributes:

GetAccess	public
SetAccess	public

Data Types: string | char

Mass — Fixed-wing aircraft mass

0 (default) | scalar numeric

Fixed-wing aircraft mass, specified as a scalar numeric, in the units:

CenterOfPressure — Location of center of pressure

[0, 0, 0] (default) | three-element vector

Location of center of pressure on the fixed-wing aircraft in the body frame, specified as a three-element vector, in these units:

Unit	Unit System
Meters (m)	'Metric'
Feet (ft)	'English (kts)' and 'English (ft/s)'

Attributes:

```

GetAccess          public
SetAccess          public

```

Data Types: string | char

AltitudeMSL — Altitude above sea level

0 (default) | scalar numeric

Altitude above sea level, specified as a scalar numeric, in these units:

Unit	Unit System
Meters (m)	'Metric'
Feet (ft)	'English (kts)' and 'English (ft/s)'

Attributes:

```

GetAccess          public
SetAccess          public

```

Data Types: string | char

GroundHeight — Ground height above sea level

0 (default) | scalar numeric

Ground height above sea level, specified as a scalar numeric in these units:

Unit	Unit System
Meters (m)	'Metric'
Feet (ft)	'English (kts)' and 'English (ft/s)'

Attributes:

```

GetAccess          public
SetAccess          public

```

Data Types: string | char

XN — North position of fixed-wing aircraft

0 (default) | scalar numeric

North position of fixed-wing aircraft, specified as a scalar numeric in these units:

Psi – Euler yaw angle

0 (default) | scalar numeric

Euler yaw angle, specified as a scalar numeric in units of radians or degrees depending on the `AngleSystem` property.

Attributes:

<code>GetAccess</code>	<code>public</code>
<code>SetAccess</code>	<code>public</code>

Data Types: `string` | `char`**P – Body roll rate**

0 (default) | scalar numeric

Body roll rate, specified as a scalar numeric in units of radians per second or degrees per second depending on the `AngleSystem` property.

Attributes:

<code>GetAccess</code>	<code>public</code>
<code>SetAccess</code>	<code>public</code>

Data Types: `string` | `char`**Q – Body pitch rate**

0 (default) | scalar numeric

Body pitch rate, specified as a scalar numeric in units of radians per second or degrees per second depending on the `AngleSystem` property.

Attributes:

<code>GetAccess</code>	<code>public</code>
<code>SetAccess</code>	<code>public</code>

Data Types: `string` | `char`**R – Body yaw rate**

0 (default) | scalar numeric

Body yaw rate, specified as a scalar numeric in units of radians per second or degrees per second depending on the `AngleSystem` property.

Attributes:

<code>GetAccess</code>	<code>public</code>
<code>SetAccess</code>	<code>public</code>

Data Types: `string` | `char`**AlphaDot – Angle of attack rate on fixed-wing aircraft**

0 (default) | scalar numeric

Angle of attack rate on fixed-wing aircraft, specified as a scalar numeric in units of radians per second or degrees per second depending on the `AngleSystem` property.

Attributes:

GetAccess public
SetAccess public

Data Types: string | char

BetaDot — Angle of sideslip rate on fixed-wing aircraft

0 (default) | scalar numeric

Angle of sideslip rate on the fixed-wing aircraft, specified as a scalar numeric in units of radians per second or degrees per second depending on the AngleSystem property.

Attributes:

GetAccess public
SetAccess public

Data Types: string | char

ControlStates — Current control state values

vector

Current control state values, specified as a vector.

Attributes:

GetAccess public
SetAccess public

Data Types: string | char

Environment — Definition of current environment

scalar

Definition of current environment, contained in an Aero.Aircraft.Environment object, specified as a scalar.

Attributes:

GetAccess public
SetAccess public

Data Types: string | char

Protected Properties**Weight — Fixed-wing aircraft weight**

scalar numeric

Fixed-wing aircraft weight, specified as a scalar numeric, in these units:

Unit	Unit System
newtons (N)	'Metric'

Attributes:

GetAccess	Restricts access
SetAccess	protected

Data Types: double

BodyVelocity – Body velocity of fixed-wing aircraft

three-element vector

Body velocity of fixed-wing aircraft, specified as a three-element vector.

BodyVelocity depends on the values of the GroundSpeed, Phi, Theta, and Psi public properties, with the equation

$$\text{BodyVelocity} = \text{GroundVelocity} - \text{InertialToBodyMatrix} * \text{Environment.WindVelocity}.$$

Attributes:

GetAccess	Restricts access
SetAccess	protected

Data Types: double

GroundVelocity – Ground velocity of fixed-wing aircraft

three-element vector

Ground velocity of the fixed-wing aircraft, specified as a three-element vector, defined with the equation

$$\text{GroundVelocity} = [U, V, W].$$

Attributes:

GetAccess	Restricts access
SetAccess	protected

Data Types: double

UR – X component of body velocity

scalar numeric

X component of body velocity, specified as scalar numeric. UR depends on *BodyVelocity*.

Attributes:

GetAccess	Restricts access
SetAccess	protected

Data Types: double

VR – Y component of body velocity

scalar numeric

Y component of body velocity, specified as scalar numeric. UR depends on *BodyVelocity*.

Attributes:

GetAccess	Restricts access
SetAccess	protected

Data Types: double

WR — Z component of body velocity

scalar numeric

Z component of body velocity, specified as scalar numeric. *UR* depends on *BodyVelocity*.

Attributes:

GetAccess	Restricts access
SetAccess	protected

Data Types: double

FlightPathAngle — Flight path angle

scalar numeric

Flight path angle, specified as a scalar numeric in units of radians or degrees depending on the *AngleSystem* property. *FlightPathAngle* is defined with the equation:

$$FlightPathAngle = \text{atan2}(W,U).$$

.

Attributes:

GetAccess	Restricts access
SetAccess	protected

Data Types: double

CourseAngle — Course angle

scalar numeric

Course angle, specified as a scalar numeric in units of radians or degrees depending on the *AngleSystem* property. *CourseAngle* depends on *V* and *U* with the equation

$$CourseAngle = \text{atan2}(V,U).$$

Attributes:

GetAccess	Restricts access
SetAccess	protected

Data Types: double

Alpha — Angle of attack

scalar numeric

Angle of attack, specified as a scalar numeric in units of radians or degrees depending on the *AngleSystem* property. *Alpha* depends on *WR* and *UR* with the equation:

$Alpha = \text{atan2}(WR, UR)$.

Attributes:

GetAccess	Restricts access
SetAccess	protected

Data Types: double

Beta – Angle of side slip

scalar numeric

Angle of side slip, specified as a scalar numeric in units of radians or degrees depends on the AngleSystem property. Beta depends on VR and Airspeed with the equation:

$Beta = \text{asin}(VR/Airspeed)$.

Attributes:

GetAccess	Restricts access
SetAccess	protected

Data Types: double

InertialToBodyMatrix – Inertial to body axes transformation matrix

3-by-3 matrix

Inertial to body axes transformation matrix, specified as a 3-by-3 matrix to convert stability axes to body axes. This property depends on the Phi, Theta, and Psi properties.

Attributes:

GetAccess	Restricts access
SetAccess	protected

Data Types: double

BodyToInertialMatrix – Body axes to stability axes transformation matrix

3-by-3 matrix

Body axes to stability axes transformation matrix, specified as a 3-by-3 matrix to convert stability axes to body axes. This property depends on the Phi, Theta, and Psi properties.

Attributes:

GetAccess	Restricts access
SetAccess	protected

Data Types: double

BodyToWindMatrix – Body to wind axes transformation matrix

3-by-3 matrix

Body to wind axes transformation matrix, specified as a 3-by-3 matrix to convert body axes to wind axes. This property depends on the Alpha and Beta properties.

Create a fixed-wing object.

```
aircraft = Aero.FixedWing()
```

```
aircraft =
```

```
FixedWing with properties:
```

```
ReferenceArea: 0
ReferenceSpan: 0
ReferenceLength: 0
Coefficients: [1x1 Aero.FixedWing.Coefficient]
DegreesOfFreedom: "6DOF"
Surfaces: [1x0 Aero.FixedWing.Surface]
Thrusts: [1x0 Aero.FixedWing.Thrust]
AspectRatio: NaN
UnitSystem: "Metric"
AngleSystem: "Radians"
TemperatureSystem: "Kelvin"
Properties: [1x1 Aero.Aircraft.Properties]
```

To define the aircraft dynamic behavior, set a coefficient for it.

```
aircraft = setCoefficient(aircraft, "CD", "Zero", 0.27)
```

```
aircraft =
```

```
FixedWing with properties:
```

```
ReferenceArea: 0
ReferenceSpan: 0
ReferenceLength: 0
Coefficients: [1x1 Aero.FixedWing.Coefficient]
DegreesOfFreedom: "6DOF"
Surfaces: [1x0 Aero.FixedWing.Surface]
Thrusts: [1x0 Aero.FixedWing.Thrust]
AspectRatio: NaN
UnitSystem: "Metric"
AngleSystem: "Radians"
TemperatureSystem: "Kelvin"
Properties: [1x1 Aero.Aircraft.Properties]
```

Define the aircraft's current state.

```
state = Aero.FixedWing.State("Mass", 500)
```

```
state =
```

```
State with properties:
```

```
Alpha: 0
Beta: 0
AlphaDot: 0
BetaDot: 0
Mass: 500
Inertia: [3x3 table]
CenterOfGravity: [0 0 0]
CenterOfPressure: [0 0 0]
AltitudeMSL: 0
```



```

GroundHeight: 0
  XN: 0
  XE: 0
  XD: 0
  U: 50
  V: 0
  W: 0
  Phi: 0
  Theta: 0
  Psi: 0
  P: 0
  Q: 0
  R: 0
  Weight: 4905
  AltitudeAGL: 0
  Airspeed: 50
  GroundSpeed: 50
  MachNumber: 0.1469
  BodyVelocity: [50 0 0]
  GroundVelocity: [50 0 0]
  Ur: 50
  Vr: 0
  Wr: 0
  FlightPathAngle: 0
  CourseAngle: 0
  InertialToBodyMatrix: [3x3 double]
  BodyToInertialMatrix: [3x3 double]
  BodyToWindMatrix: [3x3 double]
  WindToBodyMatrix: [3x3 double]
  DynamicPressure: 1.5312e+03
  Environment: [1x1 Aero.Aircraft.Environment]
  UnitSystem: "Metric"
  AngleSystem: "Radians"
  TemperatureSystem: "Kelvin"
  ControlStates: [1x0 Aero.Aircraft.ControlState]
  OutOfRangeAction: "Limit"
  DiagnosticAction: "Warning"
  Properties: [1x1 Aero.Aircraft.Properties]

```

Calculate the forces and moments on the aircraft.

```
[F, M] = forcesAndMoments(aircraft, state)
```

F =

```

  0
  0
4905

```

M =

```

  0
  0
  0

```

See Also

Aero.FixedWing | getState | setState | setupControlStates

Introduced in R2021a

Aero.FixedWing.Surface class

Package: Aero

Define aerodynamic and control surfaces on Aero.FixedWing aircraft

Description

Aero.FixedWing.Coefficient defines the dynamic and control surfaces on an Aero.FixedWing aircraft.

Class Attributes

Sealed true

For information on class attributes, see “Class Attributes”.

Creation

Description

`fixedWingSurface = Aero.FixedWing.Surface` creates a single Aero.FixedWing.Surface object with default property values.

`fixedWingSurface = Aero.FixedWing.Surface(N)` creates an N -by- N matrix of Aero.FixedWing.Surface objects with default property values.

`fixedWingSurface = Aero.FixedWing.Surface(M,N,P,...)` or `Aero.FixedWing.Surface([M N P ...])` creates an M -by- N -by- P -by-... array of Aero.FixedWing.Surface objects with default property values.

`fixedWingSurface = Aero.FixedWing.Surface(size(A))` creates an Aero.FixedWing.Surface object of the same size as A and all Aero.FixedWing.Surface objects.

`fixedWingSurface = Aero.FixedWing.Surface(__,property,propertyValue)` creates an array of Aero.FixedWing.Surface objects with *property*, *propertyValue* pairs applied to each of the Aero.FixedWing.Surface array objects. For a list of properties, see “Properties” on page 4-75.

Properties

Public Properties

Surfaces — Aero.FixedWing.Surface objects

vector

Aero.FixedWing.Surface objects providing nested control surfaces, specified as a vector.

Attributes:

GetAccess	public
SetAccess	public

Coefficients — Aero.FixedWing.Coefficients objects

scalar

Aero.FixedWing.Coefficients objects that define the control surface, specified as a scalar.

Attributes:

GetAccess	public
SetAccess	public

MaximumValue — Maximum value of control surfaces

infinity (default) | scalar numeric

Maximum value of control surfaces, specified as a scalar numeric.

Dependencies

If Symmetry is set to Asymmetric, then this value applies to both control variables.

Attributes:

GetAccess	public
SetAccess	public

Data Types: double

MinimumValue — Minimum value of control surface

negative infinity (default) | scalar numeric

Minimum value of control surface, specified as a scalar numeric.

Dependencies

If Symmetry is set to Asymmetric, then this value applies to both control variables.

Attributes:

GetAccess	public
SetAccess	public

Data Types: double

Controllable — Controllable control surface

off (default) | on

Controllable control surface specified as on or off. To control the control surface, set this property to on. Otherwise, set this property to off.

Attributes:

GetAccess	public
SetAccess	public

Data Types: logical

Symmetry — Symmetry of control surface

Symmetric (default) | Asymmetric

Symmetry of the control surface, specified as `Symmetric` or `Asymmetric`.

The `Asymmetric` option creates two control variables, denoted by the name on the properties and appended by `_1` and `_2`. These control variables can be independently controlled but also produce an effective control variable specified by the name on the properties. This equation defines the control variable:

$$name = (name_1 - name_2) / 2.$$

You cannot set this effective control variable.

Attributes:

GetAccess	public
SetAccess	public

Data Types: char | string

Properties — Aero.Aircraft.Properties object

scalar

`Aero.Aircraft.Properties` object, specified as a scalar.

Attributes:

GetAccess	public
SetAccess	public

Data Types: double

Protected Properties**ControlVariables — Control variable names**

vector

Control variable names, specified as a vector. This property depends on `Properties.Name`, `Controllable`, and `Symmetry`.

Attributes:

GetAccess	Restricts access
SetAccess	protected

Data Types: char | string

Methods**Public Methods**

getCoefficient	Get coefficient for fixed-wing surface object
getControlStates	Get control states for <code>Aero.FixedWing.Surface</code> object
setCoefficient	Set coefficient values for <code>Aero.FixedWing.Surface</code> object
update	Update <code>Aero.FixedWing.Surface</code> object

Examples

Create and Use Fixed-Wing Object

Create and set up dynamic behavior and the current state for the fixed-wing object aircraft.

Create a fixed-wing object.

```
aircraft = Aero.FixedWing()
aircraft =
    FixedWing with properties:
        ReferenceArea: 0
        ReferenceSpan: 0
        ReferenceLength: 0
        Coefficients: [1x1 Aero.FixedWing.Coefficient]
        DegreesOfFreedom: "6DOF"
        Surfaces: [1x0 Aero.FixedWing.Surface]
        Thrusts: [1x0 Aero.FixedWing.Thrust]
        AspectRatio: NaN
        UnitSystem: "Metric"
        AngleSystem: "Radians"
        TemperatureSystem: "Kelvin"
        Properties: [1x1 Aero.Aircraft.Properties]
```

To define the aircraft dynamic behavior, set a coefficient for it.

```
aircraft = setCoefficient(aircraft, "CD", "Zero", 0.27)
aircraft =
```

```
FixedWing with properties:
    ReferenceArea: 0
    ReferenceSpan: 0
    ReferenceLength: 0
    Coefficients: [1x1 Aero.FixedWing.Coefficient]
    DegreesOfFreedom: "6DOF"
    Surfaces: [1x0 Aero.FixedWing.Surface]
    Thrusts: [1x0 Aero.FixedWing.Thrust]
    AspectRatio: NaN
    UnitSystem: "Metric"
    AngleSystem: "Radians"
    TemperatureSystem: "Kelvin"
    Properties: [1x1 Aero.Aircraft.Properties]
```

Define the aircraft's current state.

```
state = Aero.FixedWing.State("Mass", 500)
state =
```

```
State with properties:
    Alpha: 0
```

```

        Beta: 0
        AlphaDot: 0
        BetaDot: 0
        Mass: 500
        Inertia: [3x3 table]
        CenterOfGravity: [0 0 0]
        CenterOfPressure: [0 0 0]
        AltitudeMSL: 0
        GroundHeight: 0
        XN: 0
        XE: 0
        XD: 0
        U: 50
        V: 0
        W: 0
        Phi: 0
        Theta: 0
        Psi: 0
        P: 0
        Q: 0
        R: 0
        Weight: 4905
        AltitudeAGL: 0
        Airspeed: 50
        GroundSpeed: 50
        MachNumber: 0.1469
        BodyVelocity: [50 0 0]
        GroundVelocity: [50 0 0]
        Ur: 50
        Vr: 0
        Wr: 0
        FlightPathAngle: 0
        CourseAngle: 0
        InertialToBodyMatrix: [3x3 double]
        BodyToInertialMatrix: [3x3 double]
        BodyToWindMatrix: [3x3 double]
        WindToBodyMatrix: [3x3 double]
        DynamicPressure: 1.5312e+03
        Environment: [1x1 Aero.Aircraft.Environment]
        UnitSystem: "Metric"
        AngleSystem: "Radians"
        TemperatureSystem: "Kelvin"
        ControlStates: [1x0 Aero.Aircraft.ControlState]
        OutOfRangeAction: "Limit"
        DiagnosticAction: "Warning"
        Properties: [1x1 Aero.Aircraft.Properties]

```

Calculate the forces and moments on the aircraft.

```
[F, M] = forcesAndMoments(aircraft, state)
```

F =

```

    0
    0
  4905

```

M =

0
0
0

Limitations

You cannot subclass `Aero.FixedWing.Surface`.

See Also

`Aero.FixedWing` | `Aero.FixedWing.Coefficient` | `Aero.FixedWing.Thrust`

Introduced in R2021a

Aero.FixedWing.Thrust class

Package: Aero

Define thrust vector on fixed-wing aircraft

Description

`Aero.FixedWing.Thrust` creates an `Aero.FixedWing` thrust vector that describes the thrust of an aircraft.

Class Attributes

Sealed true

For information on class attributes, see “Class Attributes”.

Creation

Description

`fixedWingThrust = Aero.FixedWing.Thrust` creates a single `Aero.FixedWing.Thrust` object with default property values.

`fixedWingThrust = Aero.FixedWing.Thrust(N)` creates an N -by- N matrix of `Aero.FixedWing.Thrust` objects with default property values.

`fixedWingThrust = Aero.FixedWing.Thrust(M,N,P,...)` or `Aero.FixedWing.Thrust([M N P ...])` creates an M -by- N -by- P -by-... array of `Aero.FixedWing.Thrust` objects with default property values.

`fixedWingThrust = Aero.FixedWing.Thrust(size(A))` creates an `Aero.FixedWing.Thrust` object that is the same size as `A` and all `Aero.FixedWing.Thrust` objects.

`fixedWing.Thrust = Aero.FixedWing.Thrust(__,property,propertyValue)` creates an array of `Aero.FixedWing.Thrust` objects with *property*, *propertyValue* pairs applied to each of the `Aero.FixedWing.Thrust` array objects. For a list of properties, see “Properties” on page 4-82.

Input Arguments

N — Number of fixed-wing thrust objects

scalar

Number of fixed-wing thrust objects, specified as a scalar.

M — Number of fixed-wing thrust objects

scalar

Number of fixed-wing thrust objects, specified as a scalar.

P — Number of fixed-wing thrust objects

scalar

Number of fixed-wing thrust objects, specified as a scalar.

A — Size of fixed-wing thrust object

scalar

Size of fixed-wing thrust object, specified as a scalar.

Properties

Public Properties

Coefficients — Aero.FixedWing.Coefficients object

scalar

Aero.FixedWing.Coefficients object, specified as a scalar, that defines the thrust vector.

Attributes:

GetAccess	public
SetAccess	public

MaximumValue — Maximum thrust value

1 (default) | scalar numeric

Maximum thrust value, specified as a scalar numeric.

Dependencies

If Symmetry is set to Asymmetric, then this value applies to both control variables.

Attributes:

GetAccess	public
SetAccess	public

Data Types: double

MinimumValue — Minimum thrust value

0 (default) | scalar numeric

Minimum thrust value, specified as a scalar numeric.

Dependencies

If Symmetry is set to Asymmetric, then this value applies to both control variables.

Attributes:

GetAccess	public
SetAccess	public

Data Types: double

Controllable — Controllable thrust value

on (default) | off

Controllable thrust value, specified as on or off. To control the thrust value, set this property to on. Otherwise, set this property to off.

Attributes:

GetAccess	public
SetAccess	public

Data Types: logical

Symmetry — Symmetry of thrust control

Symmetric (default) | Asymmetric

Symmetry of the thrust control, specified as `Symmetric` or `Asymmetric`.

The `Asymmetric` option creates two control variables, denoted by the name on the properties and appended by `_1` and `_2`. These control variables can be independently controlled, but also produce an effective control variable specified by the name on the properties. This equation defines the control variable:

$$name = (name_1 - name_2) / 2.$$

You cannot set this effective control variable.

Attributes:

GetAccess	public
SetAccess	public

Data Types: char | string

Properties — Aero.Aircraft.Properties object

scalar

`Aero.Aircraft.Properties` object, specified as a scalar.

Attributes:

GetAccess	public
SetAccess	public

Data Types: double

Protected Properties**ControlVariables — Control variable names**

vector

Control variable names, specified as a vector. This property depends on `Properties.Name`, `Controllable`, and `Symmetry`.

Attributes:

GetAccess	Restricts access
SetAccess	protected

Data Types: char | string

Methods

Public Methods

<code>getCoefficient</code>	Get coefficient for fixed-wing thrust object
<code>getControlStates</code>	Get control states for <code>Aero.FixedWing.Thrust</code> object
<code>setCoefficient</code>	Set coefficient values for <code>Aero.FixedWing.Thrust</code> object
<code>update</code>	Update <code>Aero.FixedWing.Thrust</code> object

Examples

Create and Use Fixed-Wing Object

Create and set up dynamic behavior and the current state for the fixed-wing object aircraft.

Create a fixed-wing object:

```
aircraft = Aero.FixedWing()
```

```
aircraft =
```

```
FixedWing with properties:
```

```
ReferenceArea: 0
ReferenceSpan: 0
ReferenceLength: 0
Coefficients: [1x1 Aero.FixedWing.Coefficient]
DegreesOfFreedom: "6DOF"
Surfaces: [1x0 Aero.FixedWing.Surface]
Thrusts: [1x0 Aero.FixedWing.Thrust]
AspectRatio: NaN
UnitSystem: "Metric"
AngleSystem: "Radians"
TemperatureSystem: "Kelvin"
Properties: [1x1 Aero.Aircraft.Properties]
```

To define the aircraft dynamic behavior, set a coefficient for it:

```
aircraft = setCoefficient(aircraft, "CD", "Zero", 0.27)
```

```
aircraft =
```

```
FixedWing with properties:
```

```
ReferenceArea: 0
ReferenceSpan: 0
ReferenceLength: 0
Coefficients: [1x1 Aero.FixedWing.Coefficient]
DegreesOfFreedom: "6DOF"
Surfaces: [1x0 Aero.FixedWing.Surface]
Thrusts: [1x0 Aero.FixedWing.Thrust]
AspectRatio: NaN
UnitSystem: "Metric"
AngleSystem: "Radians"
TemperatureSystem: "Kelvin"
Properties: [1x1 Aero.Aircraft.Properties]
```

Define aircraft current state:

```
state = Aero.FixedWing.State("Mass", 500)
```

```
state =
```

```
    State with properties:
```

```
        Alpha: 0
        Beta: 0
    AlphaDot: 0
    BetaDot: 0
        Mass: 500
        Inertia: [3x3 table]
    CenterOfGravity: [0 0 0]
    CenterOfPressure: [0 0 0]
        AltitudeMSL: 0
    GroundHeight: 0
        XN: 0
        XE: 0
        XD: 0
        U: 50
        V: 0
        W: 0
        Phi: 0
        Theta: 0
        Psi: 0
        P: 0
        Q: 0
        R: 0
        Weight: 4905
        AltitudeAGL: 0
        Airspeed: 50
        GroundSpeed: 50
        MachNumber: 0.1469
        BodyVelocity: [50 0 0]
    GroundVelocity: [50 0 0]
        Ur: 50
        Vr: 0
        Wr: 0
    FlightPathAngle: 0
        CourseAngle: 0
    InertialToBodyMatrix: [3x3 double]
    BodyToInertialMatrix: [3x3 double]
    BodyToWindMatrix: [3x3 double]
    WindToBodyMatrix: [3x3 double]
    DynamicPressure: 1.5312e+03
        Environment: [1x1 Aero.Aircraft.Environment]
        UnitSystem: "Metric"
        AngleSystem: "Radians"
    TemperatureSystem: "Kelvin"
        ControlStates: [1x0 Aero.Aircraft.ControlState]
    OutOfRangeAction: "Limit"
    DiagnosticAction: "Warning"
        Properties: [1x1 Aero.Aircraft.Properties]
```

Calculate the forces and moments on the aircraft:

```
[F, M] = forcesAndMoments(aircraft, state)
```

F =

```
    0
    0
4905
```

M =

```
0
0
0
```

Limitations

You cannot subclass `Aero.FixedWing.Thrust`.

See Also

`Aero.FixedWing` | `Aero.FixedWing.Coefficient` | `Aero.FixedWing.Thrust`

Introduced in R2021a

Aero.FlightGearAnimation

Construct FlightGear animation object

Syntax

```
h = Aero.FlightGearAnimation
```

Description

`h = Aero.FlightGearAnimation` constructs a FlightGear animation object. The FlightGear animation object is returned to `h`.

Limitations

These capabilities are not available for Aerospace Toolbox Online:

- The `Aero.FlightGearAnimation` object
- The related example, “Create a Flight Animation from Trajectory Data” on page 5-17

Constructor

Method	Description
<code>fganimation</code>	Construct FlightGear animation object.

Method Summary

Method	Description
<code>ClearTimer</code>	Clear and delete timer for animation of FlightGear flight simulator.
<code>delete</code>	Destroy FlightGear animation object.
<code>GenerateRunScript</code>	Generate run script for FlightGear flight simulator.
<code>initialize</code>	Set up FlightGear animation object.
<code>play</code>	Animate FlightGear flight simulator using given position/angle time series.
<code>SetTimer</code>	Set name of timer for animation of FlightGear flight simulator.
<code>update</code>	Update position data to FlightGear animation object.

Property Summary

Properties	Description
<code>TimeseriesSource</code>	Specify variable that contains the time series data.

Properties	Description
TimeseriesSourceType	Specify the type of time series data stored in 'TimeseriesSource'. Five values are available. They are listed in TimeseriesSourceType Properties. The default value is 'Array6DoF'.
TimeseriesReadFcn	Specify a function to read the time series data if 'TimeseriesSourceType' is 'Custom'.
TimeScaling	Specify the seconds of animation data per second of wall-clock time. The default ratio is 1.
FramesPerSecond	Specify the number of frames per second used to animate the 'TimeseriesSource'. The default value is 12 frames per second.
OutputFileName	Specify the name of the output file. The file name is the name of the command you will use to start FlightGear with these initial parameters. The default value is 'runfg.bat'.
FlightGearBase-Directory	Specify the name of your FlightGear installation folder. The default value is 'D:\Applications\FlightGear'. Note The run script file name must be composed of ASCII characters.
GeometryModelName	Specify the name of the folder containing the desired model geometry in the <i>FlightGear\data\Aircraft</i> folder. The default value is 'HL20'. Note FlightGear must be installed in a folder path name composed of ASCII characters.
DestinationIpAddress	Specify your destination IP address. The default value is '127.0.0.1'.
DestinationPort	Specify your network flight dynamics model (fdm) port. This destination port should be an unused port that you can use when you launch FlightGear. The default value is '5502'.
AirportId	Specify the airport ID. The list of supported airports is available in the FlightGear interface, under Location . The default value is 'KSF0'.
RunwayId	Specify the runway ID. The default value is '10L'.
InitialAltitude	Specify the initial altitude of the aircraft, in feet. The default value is 7224 feet.
InitialHeading	Specify the initial heading of the aircraft, in degrees. The default value is 113 degrees.
OffsetDistance	Specify the offset distance of the aircraft from the airport, in miles. The default value is 4.72 miles.
OffsetAzimuth	Specify the offset azimuth of the aircraft, in degrees. The default value is 0 degrees.
TStart	Specify start time as a double.
TFinal	Specify end time as a double.

Properties	Description
Architecture	Specify the architecture the FlightGear software is running on. GenerateRunScript takes this setting into account when generating the bash run script to start FlightGear. The platforms are listed in Architecture Properties. The default value is 'Default'.

The time series data, stored in the property 'TimeseriesSource', is interpreted according to the 'TimeseriesSourceType' property, which can be one of:

TimeseriesSourceType Properties

Property	Description
'Timeseries'	MATLAB time series data with six values per time: lat lon alt phi theta psi The values are resampled.
'StructureWithTime'	Simulink struct with time (for example, Simulink root outport logging 'Structure with time'): <ul style="list-style-type: none"> signals(1).values: lat lon alt signals(2).values: phi theta psi Signals are linearly interpolated vs. time using interp1.
'Array6DoF'	A double-precision array in n rows and 7 columns for 6-DoF data: time lat lon alt phi theta psi. If a double-precision array of 8 or more columns is in 'TimeseriesSource', the first 7 columns are used as 6-DoF data.
'Array3DoF'	A double-precision array in n rows and 4 columns for 3-DoF data: time lat alt theta. If a double-precision array of 5 or more columns is in 'TimeseriesSource', the first 4 columns are used as 3-DoF data.
'Custom'	Position and angle data is retrieved from 'TimeseriesSource' by the currently registered 'TimeseriesReadFcn'.

Specify one of these values for the Architecture property:

Architecture Properties

Property	Description
'Default'	Architecture the MATLAB software is currently running on. If the property has this value, <code>GenerateRunScript</code> creates a bash file that can work in the architecture that MATLAB is currently running on.
'Win64'	Windows (64-bit) architecture.
'Mac'	Mac OS X (64-bit) architecture.
'Linux'	Linux (64-bit) architecture.

'Default'	Architecture the MATLAB software is currently running on. If the property has this value, <code>GenerateRunScript</code> creates a bash file that can work in the architecture that MATLAB is currently running on.
'Win64'	Windows (64-bit) architecture.
'Mac'	Mac OS X (64-bit) architecture.
'Linux'	Linux (64-bit) architecture.

Examples

Construct a FlightGear animation object, h:

```
h = fanimation
```

See Also

`fanimation` | `generaterunscript` | `play`

Introduced in R2007a

aeroReadIERSData

File containing current International Astronomical Union (IAU) 2000A Earth orientation data

Syntax

```
file=aeroReadIERSData(foldername)
file=aeroReadIERSData(foldername,'url',urladdress)
```

Description

`file=aeroReadIERSData(foldername)` creates a MAT-file, `file`, based on IAU 2000A Earth orientation data from the International Earth Rotation and Reference Systems Service (IERS). It saves the file to `foldername`. `file` name has the format `aeroiersdataYYYYMMDD.mat`, where:

- YYYY - Year
- MM - Month
- DD - Day

`file=aeroReadIERSData(foldername,'url',urladdress)` creates the MAT-file based on Earth orientation data from a specific web site or data file.

Examples

Create File for Current Day

Create the Earth orientation data file for the current day, in the current folder, using data from the default web site <https://maia.usno.navy.mil/ser7/finals2000A.data>.

```
aeroReadIERSData(pwd)
```

Create File from Specified Web Site

Create the Earth orientation file for the current day, in the current folder, using data from the alternate web site https://datacenter.iers.org/data/latestVersion/10_FINALS.DATA_IAU2000_V2013_0110.txt.

```
aeroReadIERSData(pwd,'url','https://datacenter.iers.org/data/latestVersion/10_FINALS.DATA_IAU2000_V2013_0110.txt')
```

Create File from Specified File

Create the Earth orientation file for the current day, in the current folder, using data from a specified file `file:///C:\Documents\final2000A.data`.

```
aeroReadIERSData(pwd, 'url', 'file:///C:\Documents\finals2000A.data')
```

Input Arguments

foldername — Folder for IERS data file

folder name

Folder for IERS data file, specified as a character array or string. Before running this function, create *foldername* with write permission.

Data Types: char | string

'url', urladdress — Optional web site or Earth orientation data file

<https://maia.usno.navy.mil/ser7/finals2000A.data> (default) | web site address | file name

Optional web site or file containing the IAU 2000A Earth orientation data, specified as a web site address or file name.

Note If you receive an error message while accessing the default site, use one of these alternate sites:

- https://datacenter.iers.org/data/latestVersion/10_FINALS.DATA_IAU2000_V2013_0110.txt
 - <ftp://ftp.iers.org/products/eop/rapid/standard/finals2000A.data>
-

Example: https://datacenter.iers.org/data/latestVersion/10_FINALS.DATA_IAU2000_V2013_0110.txt

Data Types: char | string

Output Arguments

file — Location of Earth orientation data MAT-file

character array

Location of Earth orientation data MAT-file, specified as a character array.

More About

International Astronomical Union (IAU) 2000A Earth Orientation Data Format

The function expects the International Astronomical Union (IAU) 2000A Earth orientation data to use the format referenced here <https://maia.usno.navy.mil/ser7/finals2000A.data>:

Column	Description
1 to 2	Year (to get true calendar year, add 1900 for MJD<=51543 or add 2000 for MJD>=51544)
3 to 4	Month number
5 to 6	Day of month

Column	Description
7	Blank
8 to 15	Fractional modified Julian date (MJD UTC)
16	Blank
17	IERS (I) or Prediction (P) flag for Bull. A polar motion values*
18	Blank
19 to 27	Bull. A PM-x (sec. of arc)*
28-36	Error in PM-x (sec. of arc)*
37	Blank
38-46	Bull. A PM-y (sec. of arc)*
47-55	Error in PM-y (sec. of arc)*
56-57	Blank
58	IERS (I) or Prediction (P) flag for Bulletin A UT1-UTC values*
59-68	Bull. A UT1-UTC (sec. of time)*
69-78	Error in UT1-UTC (sec. of time)*
79	Blank
80-86	Bull. A LOD (msec. of time) -- not always filled*
87-93	Error in LOD (msec. of time) -- not always filled*
94-95	Blank
96	IERS (I) or Prediction (P) flag for Bull. A nutation values*
97	Blank
98-106	Bull. A dX wrt IAU2000A nutation (msec. of arc), free core nutation not removed*
107-115	Error in dX (msec. of arc)
116	Blank
117-125	Bull. A dY wrt IAU2000A nutation (msec. of arc), free core nutation not removed*
126-134	Error in dY (msec. of arc)
135-144	Bull. B PM-x (sec. of arc)*
145-154	Bull. B PM-x (sec. of arc)*
155-165	Bull. B UT1-UTC (sec. of time)*
166-175	Bull. B dX wrt IAU2000A nutation (msec. of arc)*
176-185	Bull. B dY wrt IAU2000A nutation (msec. of arc)*

* Abbreviated terms:

- Bull. — Bulletin

- LOD — Length of day
- wrt — With regard to
- pm — Polar motion

See Also

`dcmece2ecef` | `deltaUT1` | `eci2aer` | `eci2lla` | `lla2eci` | `mjuliandate`

Introduced in R2017b

Aero.Geometry

Construct 3-D geometry for use with animation object

Syntax

```
h = Aero.Geometry
```

Description

`h = Aero.Geometry` defines a 3-D geometry for use with an animation object.

This object supports the attachment of transparency data from an Ac3d file to patch generation.

Constructor Summary

Constructor	Description
<code>Geometry</code>	Construct 3-D geometry for use with animation object.

Method Summary

Method	Description
<code>read</code>	Read geometry data using current reader.

Property Summary

Property	Description	Values										
Name	Specify name of geometry.	Character vector string										
Source	Specify geometry data source.	{['Auto'], 'Variable', 'MatFile', 'Ac3dFile', 'Custom'}										
Reader	Specify geometry reader.	MATLAB array										
FaceVertexColorData	Specify the color of the geometry face vertex.	MATLAB structure with the following fields <table border="0" style="margin-left: 20px;"> <tr> <td>name</td> <td>Character vector or string that contains the name of the geometry being loaded.</td> </tr> <tr> <td>faces</td> <td>See Faces.</td> </tr> <tr> <td>vertices</td> <td>See Vertices.</td> </tr> <tr> <td>cdata</td> <td>See CData.</td> </tr> <tr> <td>alpha</td> <td>See FaceVertexAlphaData.</td> </tr> </table>	name	Character vector or string that contains the name of the geometry being loaded.	faces	See Faces.	vertices	See Vertices.	cdata	See CData.	alpha	See FaceVertexAlphaData.
name	Character vector or string that contains the name of the geometry being loaded.											
faces	See Faces.											
vertices	See Vertices.											
cdata	See CData.											
alpha	See FaceVertexAlphaData.											

See Also

read

Introduced in R2007a

Aero.Node

Create node object for use with virtual reality animation

Syntax

```
h = Aero.Node
```

Description

`h = Aero.Node` creates a node object for use with virtual reality animation. Typically, you do not need to create a node object with this method. This is because the `.wrl` file stores the information for a virtual reality scene. During the initialization of the virtual reality animation object, any node with a DEF statement in the specified `.wrl` file has a node object created.

When working with nodes, consider the translation and rotation. Translation is a 1-by-3 matrix in the aerospace body coordinate system defined for the `VirtualRealityAnimation` object or another coordinate system. In the latter case, you can use the `CoordTransformFcn` function to move it into the defined aerospace body coordinate system. The defined aerospace body coordinate system is defined relative to the screen as *x*-left, *y*-in, *z*-down.

Rotation is a 1-by-3 matrix, in radians, that specifies the rotations about the right-hand *x-y-z* sequence of coordinate axes. The order of application of the rotation is *z-y-x* (*r-q-p*). This function uses the `CoordTransformFcn` to apply the translation and rotation from the input coordinate system to the defined aerospace body coordinate system. The function then moves the translation and rotation from the defined aerospace body coordinate system to the defined VRML *x-y-z* coordinates for the `VirtualRealityAnimation` object. The defined VRML coordinate system is defined relative to the screen as *x*-right, *y*-up, *z*-out.

Constructor Summary

Constructor	Description
Node	Create node object for use with virtual reality animation.

Method Summary

Method	Description
<code>findstartstoptimes</code>	Return start and stop times for time series data.
<code>move</code>	Change node translation and rotation.
<code>update</code>	Change node position and orientation versus time data.

Property Summary

Property	Description	Values
Name	Specify name of the node object.	Character vector string

Property	Description	Values
VRNode	Return the handle to the vrnode object associated with the node object.	MATLAB array
CoordtransformFcn	Specify a function that controls the coordinate transformation.	MATLAB array
TimeseriesSource	Specify time series source.	MATLAB array
TimeseriesSourceType	Specify the type of time series data stored in 'TimeseriesSource'. Five values are available. They are listed in TimeseriesSourceType Properties. The default value is 'Array6DoF'.	Character vector string
TimeseriesReadFcn	Specify time series read function.	MATLAB array

The time series data, stored in the property 'TimeseriesSource', is interpreted according to the 'TimeseriesSourceType' property, which can be one of:

TimeseriesSourceType Properties

Property	Description
'Timeseries'	MATLAB time series data with six values per time: lat lon alt phi theta psi The values are resampled.
'StructureWithTime'	Simulink struct with time (for example, Simulink root output logging 'Structure with time'): <ul style="list-style-type: none"> signals(1).values: lat lon alt signals(2).values: phi theta psi Signals are linearly interpolated vs. time using interp1.
'Array6DoF'	A double-precision array in n rows and 7 columns for 6-DoF data: time lat lon alt phi theta psi. If a double-precision array of 8 or more columns is in 'TimeseriesSource', the first 7 columns are used as 6-DoF data.
'Array3DoF'	A double-precision array in n rows and 4 columns for 3-DoF data: time lat alt theta. If a double-precision array of 5 or more columns is in 'TimeseriesSource', the first 4 columns are used as 3-DoF data.
'Custom'	Position and angle data is retrieved from 'TimeseriesSource' by the currently registered 'TimeseriesReadFcn'.

Introduced in R2007b

Aero.Viewpoint

Create viewpoint object for use in virtual reality animation

Syntax

```
h = Aero.Viewpoint
```

Description

`h = Aero.Viewpoint` creates a viewpoint object for use with virtual reality animation.

Constructor Summary

Constructor	Description
Viewpoint	Create node object for use with virtual reality animation.

Property Summary

Property	Description	Values
Name	Specify name of the node object.	Character vector string
Node	Specify node object that contains the viewpoint node.	MATLAB array

Introduced in R2007b

Aero.VirtualRealityAnimation

Construct virtual reality animation object

Syntax

```
h = Aero.VirtualRealityAnimation
```

Description

`h = Aero.VirtualRealityAnimation` constructs a virtual reality animation object. The animation object is returned to `h`. The animation object has the following methods and properties.

Limitations

The `Aero.VirtualRealityAnimation` object is not available for Aerospace Toolbox Online.

Constructor Summary

Constructor	Description
<code>VirtualRealityAnimation</code>	Construct virtual reality animation object.

Method Summary

Method	Description
<code>addNode</code>	Add existing node to current virtual reality world.
<code>addRoute</code>	Add VRML ROUTE statement to virtual reality animation.
<code>addViewpoint</code>	Add viewpoint for virtual reality animation.
<code>delete</code>	Destroy virtual reality animation object.
<code>initialize</code>	Create and populate virtual reality animation object.
<code>nodeInfo</code>	Create list of nodes associated with virtual reality animation object.
<code>play</code>	Animate virtual reality world for given position and angle in time series data.
<code>removeNode</code>	Remove node from virtual reality animation object.
<code>removeViewpoint</code>	Remove viewpoint node from virtual reality animation.
<code>saveas</code>	Save virtual reality world associated with virtual reality animation object.
<code>updateNodes</code>	Set new translation and rotation of moveable items in virtual reality animation.

Notes on Aero.VirtualRealityAnimation Methods

`Aero.VirtualRealityAnimation` methods that change the current virtual reality world use a temporary `.wrl` file to manage those changes. These methods include:

- `addNode`
- `removeNode`
- `addViewpoint`
- `removeViewpoint`
- `addRoute`

Be aware of the following behavior:

- After the methods make the changes, they reinitialize the world, using the information stored in the temporary `.wrl` file.
- When you delete the virtual reality animation object, this action deletes the temporary file.
- Use the `saveas` method to save the temporary `.wrl` file.
- These methods do not affect user-created `.wrl` files.

Property Summary

Property	Description	Values
<code>Name</code>	Specify name of the animation object.	Character vector string
<code>VRWorld</code>	Returns the <code>vrworld</code> object associated with the animation object.	MATLAB array
<code>VRWorldFilename</code>	Specify the <code>.wrl</code> file for the <code>vrworld</code> .	Character vector string
<code>VRWorldOldFilename</code>	Specify the old <code>.wrl</code> files for the <code>vrworld</code> .	MATLAB array
<code>VRWorldTempFilename</code>	Specify the temporary <code>.wrl</code> file for the animation object.	Character vector string
<code>VRFigure</code>	Returns the <code>vrfigure</code> object associated with the animation object.	MATLAB array
<code>Nodes</code>	Specify the nodes that the animation object contains.	MATLAB array
<code>Viewpoints</code>	Specify the viewpoints that the animation object contains.	MATLAB array
<code>TimeScaling</code>	Specify the time scaling, in seconds.	double
<code>TStart</code>	Specify the recording start time, in seconds.	double
<code>TFinal</code>	Specify end time, in seconds.	double
<code>TCurrent</code>	Specify current time, in seconds.	double
<code>FramesPerSecond</code>	Specify rate, in frames per second.	double
<code>ShowSaveWarning</code>	Specify save warning display setting.	double <ul style="list-style-type: none"> • 0 — No warning is displayed. • Non-zero — Warning is displayed.
<code>VideoFileName</code>	Specify video recording file name.	Character vector string

Property	Description	Values
VideoCompression	Specify video recording compression file type. For more information on video compression, see VideoWriter.	<ul style="list-style-type: none"> 'Archival' Create Motion JPEG 2000 format file with lossless compression. 'Motion JPEG AVI' Create compressed AVI format file using Motion JPEG codec. 'Motion JPEG 2000' Create compressed Motion JPEG 2000 format file. 'MPEG-4' Create compressed MPEG-4 format file with H.264 encoding (Windows 7 systems only). 'Uncompressed AVI' Create uncompressed AVI format file with RGB24 video. Aero.VideoProfileTypeEnum Default: 'Archival'
VideoQuality	Specify video recording quality. For more information on video quality, see the Quality property of VideoWriter.	Value between 0 and 100. double Default: 75
VideoRecord	Enable video recording.	<ul style="list-style-type: none"> 'on' Enable video recording. 'off' Disable video recording. 'scheduled' Schedule video recording. Use this property with the VideoTStart and VideoTFinal properties. Default: 'off'
VideoTStart	Specify video recording start time for scheduled recording.	Value between TStart and TFinal. double Default: NaN, which uses the value of TStart.

Property	Description	Values
VideoTFinal	Specify video recording stop time for scheduled recording.	Value between TStart and TFinal. double Default: NaN, which uses the value of TFinal.

Examples

Record Virtual Reality Animation Object Simulation

This example shows how to record virtual reality animation of an object simulation.

- Record the simulation of a virtual reality animation object
- Simulate and record flight data
- Create an animation object

```

h = Aero.VirtualRealityAnimation;
% Control the frame display rate.

h.FramesPerSecond = 10;

% Configure the animation object to set the seconds of animation data per
% second time scaling (TimeScaling) property.

h.TimeScaling = 5;

% The combination of FramesPerSecond and TimeScaling property determine the
% time step of the simulation. These settings result in a time step of
% approximately 0.5 s.
% This code sets the .wrl file to use in the virtual reality animation.

h.VRWorldFilename = [matlabroot, '/toolbox/aero/astdemos/asttkoff.wrl'];

% Copy the .wrl file to a temporary directory and set the world file name
% to the copied .wrl file.

copyfile(h.VRWorldFilename, [tempdir, 'asttkoff.wrl'], 'f');
h.VRWorldFilename = [tempdir, 'asttkoff.wrl'];

% Load the animation world described in the 'VRWorldFilename' field of the
% animation object.

h.initialize();

% Set simulation timeseries data. takeoffData.mat contains logged simulated
% data. takeoffData is set up as a 'StructureWithTime', which is one of the
% default data formats.

load takeoffData
[~, idxPlane] = find(strcmp('Plane', h.nodeInfo));
h.Nodes{idxPlane}.TimeseriesSource = takeoffData;
h.Nodes{idxPlane}.TimeseriesSourceType = 'StructureWithTime';

% Use the example custom function vranimCustomTransform to correctly line
% up the position and rotation data with the surrounding objects in the
% virtual world. This code sets the coordinate transformation function for
% the virtual reality animation.

h.Nodes{idxPlane}.CoordTransformFcn = @vranimCustomTransform;

% Set up recording properties.

```



```

h.VideoRecord = 'on';
h.VideoQuality = 50;
h.VideoCompression = 'Motion JPEG AVI'
h.VideoFilename = 'astMotion_JPEG_VR';

% Play the animation.

h.play();

% Verify that a file named astMotion_JPEG_VR.avi was created in the current folder.
% Disable recording to preserve the file.

h.VideoRecord = 'off';

```

Record Virtual Reality Animation for Four Seconds

This example shows how to simulate flight data for four seconds.

```

% Create an animation object.
h = Aero.VirtualRealityAnimation;

% Control the frame display rate.
h.FramesPerSecond = 10;

% Configure the animation object to set the seconds of animation data per
% second time scaling (TimeScaling) property.
h.TimeScaling = 5;

% The combination of FramesPerSecond and TimeScaling properties determines
% the time step of the simulation. These settings result in a time step of
% approximately 0.5 s.
% This code sets the .wrl file to use in the virtual reality animation.
h.VRWorldFilename = [matlabroot, '/toolbox/aero/astdemos/asttkoff.wrl'];

% Copy the .wrl file to a temporary directory and set the world file name
% to the copied .wrl file.
copyfile(h.VRWorldFilename, [tempdir, 'asttkoff.wrl'], 'f');
h.VRWorldFilename = [tempdir, 'asttkoff.wrl'];

% Load the animation world described in the 'VRWorldFilename' field of the
% animation object.
h.initialize();

% Set simulation timeseries data. takeoffData.mat contains logged simulated
% data. takeoffData is set up as a 'StructureWithTime', which is one of the
% default data formats.
load takeoffData
[-, idxPlane] = find(strcmp('Plane', h.nodeInfo));
h.Nodes{idxPlane}.TimeseriesSource = takeoffData;
h.Nodes{idxPlane}.TimeseriesSourceType = 'StructureWithTime';

% Use the example custom function vranimCustomTransform to correctly line
% up the position and rotation data with the surrounding objects in the
% virtual world. This code sets the coordinate transformation function for
% the virtual reality animation.
h.Nodes{idxPlane}.CoordTransformFcn = @vranimCustomTransform;

% Set up recording properties.
h.VideoRecord = 'on';
h.VideoQuality = 50;
h.VideoCompression = 'Motion JPEG AVI'
h.VideoFilename = 'astMotion_JPEG';

% Play the animation from TFinal to TStart.
h.TStart = 1;
h.TFinal = 5;
h.play();

% Verify that a file named astMotion_JPEG_VR.avi was created in the
% current folder. When you rerun the recording, notice that the play time
% is faster than when you record for the length of the simulation time.

```

```
% Disable recording to preserve the file.
h.VideoRecord = 'off';
```

Schedule Three Second Recording of Virtual Reality Object Simulation

This example shows how to schedule a three second recording a virtual reality object animation simulation.

```
% Create an animation object.
h = Aero.VirtualRealityAnimation;

% Control the frame display rate.
h.FramesPerSecond = 10;

% Configure the animation object to set the seconds of animation data per
% second time scaling (TimeScaling) property.
h.TimeScaling = 5;

% The combination of FramesPerSecond and TimeScaling properties determines
% the time step of the simulation. These settings result in a time step of
% approximately 0.5 s.
% This code sets the .wrl file to use in the virtual reality animation.
h.VRWorldFilename = [matlabroot, '/toolbox/aero/astdemos/asttkoff.wrl'];

% Copy the .wrl file to a temporary directory and set the world file name
% to the copied .wrl file.
copyfile(h.VRWorldFilename, [tempdir, 'asttkoff.wrl'], 'f');
h.VRWorldFilename = [tempdir, 'asttkoff.wrl'];

% Load the animation world described in the 'VRWorldFilename' field of the
% animation object.
h.initialize();

% Set simulation timeseries data. takeoffData.mat contains logged
% simulated data. takeoffData is set up as a 'StructureWithTime', which is
% one of the default data formats.
load takeoffData
[-, idxPlane] = find(strcmp('Plane', h.nodeInfo));
h.Nodes{idxPlane}.TimeseriesSource = takeoffData;
h.Nodes{idxPlane}.TimeseriesSourceType = 'StructureWithTime';

% Use the example custom function vranimCustomTransform to correctly line
% up the position and rotation data with the surrounding objects in the
% virtual world. This code sets the coordinate transformation function for
% the virtual reality animation.
h.Nodes{idxPlane}.CoordTransformFcn = @vranimCustomTransform;

% Set up recording properties.
h.VideoQuality = 50;
h.VideoCompression = 'Motion JPEG AVI';
h.VideoFilename = 'astMotion_JPEG';

% Set up simulation time from TFinal to TStart.
h.TStart = 1;
h.TFinal = 5;

% Set up to record between two and four seconds of the four second
% simulation.
h.VideoRecord='scheduled';
h.VideoTStart = 2;
h.VideoTFinal = 4;

% Play the animation.
h.play();

% Verify that a file named astMotion_JPEG_VR.avi was created in the
% current folder. When you rerun the recording, notice that the play time
% is faster than when you record for the length of the simulation time.
```

```
% Disable recording to preserve the file.  
h.VideoRecord = 'off';
```

Introduced in R2007b

airspeed

Airspeed from velocity

Syntax

```
airspeed = airspeed(velocities)
```

Description

`airspeed = airspeed(velocities)` computes airspeeds, `airspeed`, from an m -by-3 array of Cartesian velocity vectors, `velocities`.

Examples

Determine Airspeed for One Velocity Array

Determine the airspeed for one velocity vector:

```
as = airspeed([84.3905 33.7562 10.1269])
```

```
as =
```

```
91.4538
```

Determine Airspeed for Multiple Velocity Arrays

Determine the airspeed for multiple velocity vectors:

```
as = airspeed([50 20 6; 5 0.5 2])
```

```
as =
```

```
54.1849  
5.4083
```

Input Arguments

velocities — Cartesian velocity vectors

m -by-3 array | vector

Cartesian velocity vectors, specified as an m -by-3 array.

Data Types: double

Output Arguments

airspeed — Airspeed

scalar | vector

Airspeed, returned as a scalar or array of m airspeeds.

See Also

`alpha` | `correctairspeed` | `dpressure` | `machnumber`

Introduced in R2006b

AirspeedIndicator Properties

Control airspeed indicator appearance and behavior

Description

Airspeed indicators are components that represent an airspeed indicator. Properties control the appearance and behavior of an airspeed indicator. Use dot notation to refer to a particular object and property:

```
f = uifigure;
airspeed = uiaeroairspeed(f);
airspeed.Airspeed = 100;
```

By default, minor ticks represent 10-knot increments and major ticks represent 40-knot increments. The parameters **Minimum** and **Maximum** determine the minimum and maximum values on the gauge. The number and distribution of ticks is fixed, which means that the first and last tick display the minimum and maximum values. The ticks in between distribute evenly between the minimum and maximum values. For major ticks, the distribution of ticks is $(\mathbf{Maximum-Minimum})/9$. For minor ticks, the distribution of ticks is $(\mathbf{Maximum-Minimum})/36$.

The airspeed indicator has scale color bars that allow for overlapping for the first bar, displayed at a different radius. This different radius lets the block represent maximum speed with flap extended (V_{FE}) and stall speed with flap extended (V_{SO}) accurately for aircraft airspeed and stall speed.

Properties

Airspeed Indicator

Airspeed — Airspeed

0 (default) | finite, real, and scalar numeric

Airspeed value, specified as a finite, real, and scalar numeric, in knots. The airspeed value determines the airspeed of the aircraft.

- If the value is less than the minimum **Limits** property value, then the needle points to a location immediately before the beginning of the scale.
- If the value is more than the maximum **Limits** property value, then the needle points to a location immediately after the end of the scale.

Example: 100

Limits — Minimum and maximum airspeed indicator scale values

[40 400] (default) | two-element finite and real numeric array

Minimum and maximum gauge scale values, specified as a two-element numeric array. The first value in the array must be less than the second value, in knots.

If you change **Limits** such that the **Value** property is less than the new lower limit, or more than the new upper limit, then the gauge needle points to a location off the scale.

For example, suppose `Limits` is `[0 100]` and the `Value` property is 20. If the `Limits` changes to `[50 100]`, then the needle points to a location off the scale, slightly less than 50.

ScaleColors — Scale colors

`[]` (default) | 1-by-n string array | 1-by-n cell array | n-by-3 array of RGB triplets | hexadecimal color code | ...

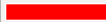



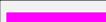



Scale colors, specified as one of the following arrays:

- A 1-by-n string array of color options, such as `["blue" "green" "red"]`.
- An n-by-3 array of RGB triplets, such as `[0 0 1;1 1 0]`.
- A 1-by-n cell array containing RGB triplets, hexadecimal color codes, or named color options. For example, `{'#EDB120', '#7E2F8E', '#77AC30'}`.







RGB triplets and hexadecimal color codes are useful for specifying custom colors.


- An RGB triplet is a three-element row vector whose elements specify the intensities of the red, green, and blue components of the color. The intensities must be in the range `[0, 1]`; for example, `[0.4 0.6 0.7]`.
- A hexadecimal color code is a character vector or a string scalar that starts with a hash symbol (`#`) followed by three or six hexadecimal digits, which can range from `0` to `F`. The values are not case sensitive. Thus, the color codes `'#FF8800'`, `'#ff8800'`, `'#F80'`, and `'#f80'` are equivalent.

Alternatively, you can specify some common colors by name. This table lists the named color options, the equivalent RGB triplets, and hexadecimal color codes.

Color Name	Short Name	RGB Triplet	Hexadecimal Color Code	Appearance
'red'	'r'	[1 0 0]	'#FF0000'	
'green'	'g'	[0 1 0]	'#00FF00'	
'blue'	'b'	[0 0 1]	'#0000FF'	
'cyan'	'c'	[0 1 1]	'#00FFFF'	
'magenta'	'm'	[1 0 1]	'#FF00FF'	
'yellow'	'y'	[1 1 0]	'#FFFF00'	
'black'	'k'	[0 0 0]	'#000000'	
'white'	'w'	[1 1 1]	'#FFFFFF'	

Here are the RGB triplets and hexadecimal color codes for the default colors MATLAB uses in many types of plots.

RGB Triplet	Hexadecimal Color Code	Appearance
[0 0.4470 0.7410]	'#0072BD'	
[0.8500 0.3250 0.0980]	'#D95319'	
[0.9290 0.6940 0.1250]	'#EDB120'	
[0.4940 0.1840 0.5560]	'#7E2F8E'	
[0.4660 0.6740 0.1880]	'#77AC30'	
[0.3010 0.7450 0.9330]	'#4DBEEE'	

RGB Triplet	Hexadecimal Color Code	Appearance
[0.6350 0.0780 0.1840]	'#A2142F'	

Each color of the `ScaleColors` array corresponds to a colored section of the gauge. Set the `ScaleColorLimits` property to map the colors to specific sections of the gauge.

If you do not set the `ScaleColorLimits` property, MATLAB distributes the colors equally over the range of the gauge.

ScaleColorLimits — Scale color limits

[] (default) | n-by-2 array

Scale color limits, specified as an n-by-2 array of numeric values. For every row in the array, the first element must be less than the second element. The first `ScaleColorLimits` value can overlap (see “Display Flight Trajectory Data Using Flight Instruments and Flight Animation” on page 5-111).

When applying colors to the gauge, MATLAB applies the colors starting with the first color in the `ScaleColors` array. Therefore, if two rows in `ScaleColorLimits` array overlap, then the color applied later takes precedence.

The gauge does not display any portion of the `ScaleColorLimits` that falls outside of the `Limits` property.

If the `ScaleColors` and `ScaleColorLimits` property values are different sizes, then the gauge shows only the colors that have matching limits. For example, if the `ScaleColors` array has three colors, but the `ScaleColorLimits` has only two rows, then the gauge displays the first two color/limit pairs only.

Value — Airspeed

0 (default) | finite, real, and scalar numeric

Airspeed value, specified as a finite, real, and scalar numeric. The airspeed value determines the airspeed of the aircraft.

- If the value is less than the minimum `Limits` property value, then the needle points to a location immediately before the beginning of the scale.
- If the value is more than the maximum `Limits` property value, then the needle points to a location immediately after the end of the scale.

Example: 100

Interactivity

Visible — Visibility of airspeed indicator

'on' (default) | on/off logical value

Visibility of the airspeed indicator, specified as 'on' or 'off', or as numeric or logical 1 (true) or 0 (false). A value of 'on' is equivalent to `true`, and 'off' is equivalent to `false`. Thus, you can use the value of this property as a logical value. The value is stored as an on/off logical value of type `matlab.lang.OnOffSwitchState`. The `Visible` property determines whether the airspeed indicator is displayed on the screen. If the `Visible` property is set to 'off', then the entire airspeed indicator is hidden, but you can still specify and access its properties.

ContextMenu — Context menu

empty GraphicsPlaceholder array (default) | ContextMenu object

Context menu, specified as a ContextMenu object created using the `uicontextmenu` function. Use this property to display a context menu when you right-click on a component.

Enable — Operational state of airspeed indicator

'on' (default) | on/off logical value

Operational state of airspeed indicator, specified as 'on' or 'off', or as numeric or logical 1 (true) or 0 (false). A value of 'on' is equivalent to true, and 'off' is equivalent to false. Thus, you can use the value of this property as a logical value. The value is stored as an on/off logical value of type `matlab.lang.OnOffSwitchState`.

- If you set this property to 'on', then the appearance of the indicator indicates that the indicator is operational.
- If you set this property to 'off', then the appearance of the indicator appears dimmed, indicating that the indicator is not operational.

Position**Position — Location and size of airspeed indicator**

[100 100 120 120] (default) | [left bottom width height]

Location and size of the airspeed indicator relative to the parent container, specified as the vector, [left bottom width height]. This table describes each element in the vector.

Element	Description
left	Distance from the inner left edge of the parent container to the outer left edge of an imaginary box surrounding the airspeed indicator
bottom	Distance from the inner bottom edge of the parent container to the outer bottom edge of an imaginary box surrounding the airspeed indicator
width	Distance between the right and left outer edges of the airspeed indicator
height	Distance between the top and bottom outer edges of the airspeed indicator

All measurements are in pixel units.

The Position values are relative to the drawable area of the parent container. The drawable area is the area inside the borders of the container and does not include the area occupied by decorations such as a menu bar or title.

Example: [200 120 120 120]

InnerPosition — Inner location and size of airspeed indicator

[100 100 120 120] (default) | [left bottom width height]

Inner location and size of the airspeed indicator, specified as [left bottom width height]. Position values are relative to the parent container. All measurements are in pixel units. This property value is identical to the Position property.

OuterPosition — Outer location and size of airspeed indicator`[100 100 120 120]] (default) | [left bottom width height]`

This property is read-only.

Outer location and size of the airspeed indicator returned as `[left bottom width height]`. Position values are relative to the parent container. All measurements are in pixel units. This property value is identical to the `Position` property.

Layout — Layout options`empty GridLayoutOptions array (default) | GridLayoutOptions object`

Layout options, specified as a `GridLayoutOptions` object. This property specifies options for components that are children of grid layout containers. If the component is not a child of a grid layout container (for example, it is a child of a figure or panel), then this property is empty and has no effect. However, if the component is a child of a grid layout container, you can place the component in the desired row and column of the grid by setting the `Row` and `Column` properties on the `GridLayoutOptions` object.

For example, this code places an airspeed indicator in the third row and second column of its parent grid.

```
g = ui([4 3]);  
gauge = uiaeroairspeed(g);  
gauge.Layout.Row = 3;  
gauge.Layout.Column = 2;
```

To make the airspeed indicator span multiple rows or columns, specify the `Row` or `Column` property as a two-element vector. For example, this airspeed indicator spans columns 2 through 3:

```
gauge.Layout.Column = [2 3];
```

Callbacks**CreateFcn — Creation function**`'' (default) | function handle | cell array | character vector`

Object creation function, specified as one of these values:

- Function handle.
- Cell array in which the first element is a function handle. Subsequent elements in the cell array are the arguments to pass to the callback function.
- Character vector containing a valid MATLAB expression (not recommended). MATLAB evaluates this expression in the base workspace.

For more information about specifying a callback as a function handle, cell array, or character vector, see “Write Callbacks in App Designer”.

This property specifies a callback function to execute when MATLAB creates the object. MATLAB initializes all property values before executing the `CreateFcn` callback. If you do not specify the `CreateFcn` property, then MATLAB executes a default creation function.

Setting the `CreateFcn` property on an existing component has no effect.

If you specify this property as a function handle or cell array, you can access the object that is being created using the first argument of the callback function. Otherwise, use the `gcbo` function to access the object.

DeleteFcn — Deletion function

' ' (default) | function handle | cell array | character vector

Object deletion function, specified as one of these values:

- Function handle.
- Cell array in which the first element is a function handle. Subsequent elements in the cell array are the arguments to pass to the callback function.
- Character vector containing a valid MATLAB expression (not recommended). MATLAB evaluates this expression in the base workspace.

For more information about specifying a callback as a function handle, cell array, or character vector, see “Write Callbacks in App Designer”.

This property specifies a callback function to execute when MATLAB deletes the object. MATLAB executes the `DeleteFcn` callback before destroying the properties of the object. If you do not specify the `DeleteFcn` property, then MATLAB executes a default deletion function.

If you specify this property as a function handle or cell array, you can access the object that is being deleted using the first argument of the callback function. Otherwise, use the `gcbo` function to access the object.

Callback Execution Control

Interruptible — Callback interruption

'on' (default) | on/off logical value

Callback interruption, specified as 'on' or 'off', or as numeric or logical 1 (true) or 0 (false). A value of 'on' is equivalent to true, and 'off' is equivalent to false. Thus, you can use the value of this property as a logical value. The value is stored as an on/off logical value of type `matlab.lang.OnOffSwitchState`.

This property determines if a running callback can be interrupted. There are two callback states to consider:

- The running callback is the currently executing callback.
- The interrupting callback is a callback that tries to interrupt the running callback.

Whenever MATLAB invokes a callback, that callback attempts to interrupt the running callback (if one exists). The `Interruptible` property of the object owning the running callback determines if interruption is allowed.

- A value of 'on' allows other callbacks to interrupt the object's callbacks. The interruption occurs at the next point where MATLAB processes the queue, such as when there is a `drawnow`, `figure`, `uifigure`, `getframe`, `waitfor`, or `pause` command.
 - If the running callback contains one of those commands, then MATLAB stops the execution of the callback at that point and executes the interrupting callback. MATLAB resumes executing the running callback when the interrupting callback completes.

- If the running callback does not contain one of those commands, then MATLAB finishes executing the callback without interruption.
- A value of 'off' blocks all interruption attempts. The `BusyAction` property of the object owning the interrupting callback determines if the interrupting callback is discarded or put into a queue.

Note Callback interruption and execution behave differently in these situations:

- If the interrupting callback is a `DeleteFcn`, `CloseRequestFcn` or `SizeChangedFcn` callback, then the interruption occurs regardless of the `Interruptible` property value.
- If the running callback is currently executing the `waitfor` function, then the interruption occurs regardless of the `Interruptible` property value.
- Timer objects execute according to schedule regardless of the `Interruptible` property value.

When an interruption occurs, MATLAB does not save the state of properties or the display. For example, the object returned by the `gca` or `gcf` command might change when another callback executes.

BusyAction — Callback queuing

'queue' (default) | 'cancel'

Callback queuing, specified as 'queue' or 'cancel'. The `BusyAction` property determines how MATLAB handles the execution of interrupting callbacks. There are two callback states to consider:

- The running callback is the currently executing callback.
- The interrupting callback is a callback that tries to interrupt the running callback.

Whenever MATLAB invokes a callback, that callback attempts to interrupt a running callback. The `Interruptible` property of the object owning the running callback determines if interruption is permitted. If interruption is not permitted, then the `BusyAction` property of the object owning the interrupting callback determines if it is discarded or put in the queue. These are possible values of the `BusyAction` property:

- 'queue' — Puts the interrupting callback in a queue to be processed after the running callback finishes execution.
- 'cancel' — Does not execute the interrupting callback.

BeingDeleted — Deletion status

on/off logical value

This property is read-only.

Deletion status, returned as an on/off logical value of type `matlab.lang.OnOffSwitchState`.

MATLAB sets the `BeingDeleted` property to 'on' when the `DeleteFcn` callback begins execution. The `BeingDeleted` property remains set to 'on' until the component object no longer exists.

Check the value of the `BeingDeleted` property to verify that the object is not about to be deleted before querying or modifying it.

Parent/Child**HandleVisibility — Visibility of object handle**

'on' (default) | 'callback' | 'off'

Visibility of the object handle, specified as 'on', 'callback', or 'off'.

This property controls the visibility of the object in its parent's list of children. When an object is not visible in its parent's list of children, it is not returned by functions that obtain objects by searching the object hierarchy or querying properties. These functions include `get`, `findobj`, `clf`, and `close`. Objects are valid even if they are not visible. If you can access an object, you can set and get its properties, and pass it to any function that operates on objects.

HandleVisibility Value	Description
'on'	The object is always visible.
'callback'	The object is visible from within callbacks or functions invoked by callbacks, but not from within functions invoked from the command line. This option blocks access to the object at the command-line, but allows callback functions to access it.
'off'	The object is invisible at all times. This option is useful for preventing unintended changes to the UI by another function. Set the <code>HandleVisibility</code> to 'off' to temporarily hide the object during the execution of that function.

Parent — Parent container

Figure object (default) | Panel object | Tab object | ButtonGroup object | GridLayout object

Parent container, specified as a `Figure` object created using the `uifigure` function, or one of its child containers: `Tab`, `Panel`, `ButtonGroup`, or `GridLayout`. If no container is specified, MATLAB calls the `uifigure` function to create a new `Figure` object that serves as the parent container.

Identifiers**Tag — Object identifier**

' ' (default) | character vector | string scalar

Object identifier, specified as a character vector or string scalar. You can specify a unique `Tag` value to serve as an identifier for an object. When you need access to the object elsewhere in your code, you can use the `findobj` function to search for the object based on the `Tag` value.

Type — Type of graphics object

'uiaeroairspeed'

This property is read-only.

Type of graphics object, returned as 'uiaeroairspeed'.

UserData — User data

[] (default) | array

User data, specified as any MATLAB array. For example, you can specify a scalar, vector, matrix, cell array, character array, table, or structure. Use this property to store arbitrary data on an object.

If you are working in App Designer, create public or private properties in the app to share data instead of using the `UserData` property. For more information, see “Share Data Within App Designer Apps”.

See Also

`uiaeroairspeed`

Topics

“Create and Configure Flight Instrument Component and an Animation Object” on page 2-49

“Display Flight Trajectory Data Using Flight Instruments and Flight Animation” on page 5-111

Introduced in R2018b

alphaBeta

Incidence and sideslip angles

Syntax

```
[incidence sideslip] = alphaBeta(velocities)
```

Description

`[incidence sideslip] = alphaBeta(velocities)` computes m incidence and sideslip angles, *incidence* and *sideslip*, between the velocity vector and the body. *velocities* is an m -by-3 array of velocities in body axes. *incidence* and *sideslip* are in radians.

Examples

Determine the incidence and sideslip angles for velocity for one array:

```
[alpha, beta] = alphaBeta([84.3905 33.7562 10.1269])
```

```
alpha =
```

```
0.1194
```

```
beta =
```

```
0.3780
```

Determine the incidence and sideslip angles for velocity for two arrays:

```
[alpha, beta] = alphaBeta([50 20 6; 5 0.5 2])
```

```
alpha =
```

```
0.1194
0.3805
```

```
beta =
```

```
0.3780
0.0926
```

See Also

[airspeed](#) | [machnumber](#)

Introduced in R2006b

Altimeter Properties

Control altimeter appearance and behavior

Description

Altimeters are components that represent an altimeter. Properties control the appearance and behavior of an altimeter. Use dot notation to refer to a particular object and property:

```
f = uifigure;
altimeter = uiaeroaltimeter(f);
altimeter.Altitude = 100;
```

The altimeter displays the altitude above sea level in feet, also known as the pressure altitude. It displays the altitude value with needles on a gauge and a numeric indicator.

- The gauge has 10 major ticks. Within each major tick are five minor ticks. This gauge has three needles. Using the needles, the altimeter can display accurately only altitudes between 0 and 100,000 feet.
 - For the longest needle, an increment of a small tick represents 20 feet and a major tick represents 100 feet.
 - For the second longest needle, a minor tick represents 200 feet and a major tick represents 1,000 feet.
 - For the shortest needle a minor tick represents 2,000 feet and a major tick represents 10,000 feet.
- For the numeric display, the gauge shows values as numeric characters between 0 and 9,999 feet. When the numeric display value reaches 10,000 feet, the gauge displays the value as the remaining values below 10,000 feet. For example, 12,345 feet displays as 2,345 feet. When a value is less than 0 (below sea level), the gauge displays 0. The needles show the appropriate value except for when the value is below sea level or over 100,000 feet. Below sea level, the needles set to 0, over 100,000, the needles stay set at 100,000.

Properties

Altimeter

Altitude — Altitude of aircraft

0 (default) | finite, real, and scalar numeric

Altitude of the aircraft, specified as any finite and scalar numeric, in feet.

Example: 60

Dependencies

Specifying this value changes the value of `Value`.

Data Types: `double`

Value — Location of aircraft heading

0 (default) | finite, real, and scalar numeric

Location of the aircraft altitude, specified as a finite and scalar numeric, in feet.

- Changing the value changes the direction of the heading in 5-degree increments.

Example: 60

Dependencies

Specifying this value changes the value of the `Altitude` value.

Data Types: `double`

Interactivity

Visible – Visibility of altimeter

'on' (default) | on/off logical value

Visibility of the altimeter, specified as 'on' or 'off', or as numeric or logical 1 (true) or 0 (false). A value of 'on' is equivalent to true, and 'off' is equivalent to false. Thus, you can use the value of this property as a logical value. The value is stored as an on/off logical value of type `matlab.lang.OnOffSwitchState`. The `Visible` property determines whether the altimeter is displayed on the screen. If the `Visible` property is set to 'off', then the entire altimeter is hidden, but you can still specify and access its properties.

ContextMenu – Context menu

empty `GraphicsPlaceholder` array (default) | `ContextMenu` object

Context menu, specified as a `ContextMenu` object created using the `uicontextmenu` function. Use this property to display a context menu when you right-click on a component.

Enable – Operational state of altimeter

'on' (default) | on/off logical value

Operational state of altimeter, specified as 'on' or 'off', or as numeric or logical 1 (true) or 0 (false). A value of 'on' is equivalent to true, and 'off' is equivalent to false. Thus, you can use the value of this property as a logical value. The value is stored as an on/off logical value of type `matlab.lang.OnOffSwitchState`.

- If you set this property to 'on', then the appearance of the altimeter indicates that the altimeter is operational.
- If you set this property to 'off', then the appearance of the altimeter appears dimmed, indicating that the altimeter is not operational.

Position

Position – Location and size of altimeter

[100 100 120 120] (default) | [left bottom width height]

Location and size of the altimeter relative to the parent container, specified as the vector, [left bottom width height]. This table describes each element in the vector.

Element	Description
left	Distance from the inner left edge of the parent container to the outer left edge of an imaginary box surrounding the altimeter

Element	Description
bottom	Distance from the inner bottom edge of the parent container to the outer bottom edge of an imaginary box surrounding the altimeter
width	Distance between the right and left outer edges of the altimeter
height	Distance between the top and bottom outer edges of the altimeter

All measurements are in pixel units.

The **Position** values are relative to the drawable area of the parent container. The drawable area is the area inside the borders of the container and does not include the area occupied by decorations such as a menu bar or title.

Example: `[200 120 120 120]`

InnerPosition — Inner location and size of altimeter

`[100 100 120 120]` (default) | `[left bottom width height]`

Inner location and size of the altimeter, specified as `[left bottom width height]`. Position values are relative to the parent container. All measurements are in pixel units. This property value is identical to the **Position** property.

OuterPosition — Outer location and size of altimeter

`[100 100 120 120]` (default) | `[left bottom width height]`

This property is read-only.

Outer location and size of the altimeter returned as `[left bottom width height]`. Position values are relative to the parent container. All measurements are in pixel units. This property value is identical to the **Position** property.

Layout — Layout options

empty `LayoutOptions` array (default) | `GridLayoutOptions` object

Layout options, specified as a `GridLayoutOptions` object. This property specifies options for components that are children of grid layout containers. If the component is not a child of a grid layout container (for example, it is a child of a figure or panel), then this property is empty and has no effect. However, if the component is a child of a grid layout container, you can place the component in the desired row and column of the grid by setting the `Row` and `Column` properties on the `GridLayoutOptions` object.

For example, this code places an altimeter in the third row and second column of its parent grid.

```
g = uigridlayout([4 3]);
gauge = uiaeroaltimeter(g);
gauge.Layout.Row = 3;
gauge.Layout.Column = 2;
```

To make the altimeter span multiple rows or columns, specify the `Row` or `Column` property as a two-element vector. For example, this altimeter spans columns 2 through 3:

```
gauge.Layout.Column = [2 3];
```

Callbacks

CreateFcn — Creation function

' ' (default) | function handle | cell array | character vector

Object creation function, specified as one of these values:

- Function handle.
- Cell array in which the first element is a function handle. Subsequent elements in the cell array are the arguments to pass to the callback function.
- Character vector containing a valid MATLAB expression (not recommended). MATLAB evaluates this expression in the base workspace.

For more information about specifying a callback as a function handle, cell array, or character vector, see “Write Callbacks in App Designer”.

This property specifies a callback function to execute when MATLAB creates the object. MATLAB initializes all property values before executing the `CreateFcn` callback. If you do not specify the `CreateFcn` property, then MATLAB executes a default creation function.

Setting the `CreateFcn` property on an existing component has no effect.

If you specify this property as a function handle or cell array, you can access the object that is being created using the first argument of the callback function. Otherwise, use the `gcbo` function to access the object.

DeleteFcn — Deletion function

' ' (default) | function handle | cell array | character vector

Object deletion function, specified as one of these values:

- Function handle.
- Cell array in which the first element is a function handle. Subsequent elements in the cell array are the arguments to pass to the callback function.
- Character vector containing a valid MATLAB expression (not recommended). MATLAB evaluates this expression in the base workspace.

For more information about specifying a callback as a function handle, cell array, or character vector, see “Write Callbacks in App Designer”.

This property specifies a callback function to execute when MATLAB deletes the object. MATLAB executes the `DeleteFcn` callback before destroying the properties of the object. If you do not specify the `DeleteFcn` property, then MATLAB executes a default deletion function.

If you specify this property as a function handle or cell array, you can access the object that is being deleted using the first argument of the callback function. Otherwise, use the `gcbo` function to access the object.

Callback Execution Control

Interruptible — Callback interruption

' on ' (default) | on/off logical value

Callback interruption, specified as 'on' or 'off', or as numeric or logical 1 (true) or 0 (false). A value of 'on' is equivalent to true, and 'off' is equivalent to false. Thus, you can use the value

of this property as a logical value. The value is stored as an on/off logical value of type `matlab.lang.OnOffSwitchState`.

This property determines if a running callback can be interrupted. There are two callback states to consider:

- The running callback is the currently executing callback.
- The interrupting callback is a callback that tries to interrupt the running callback.

Whenever MATLAB invokes a callback, that callback attempts to interrupt the running callback (if one exists). The `Interruptible` property of the object owning the running callback determines if interruption is allowed.

- A value of 'on' allows other callbacks to interrupt the object's callbacks. The interruption occurs at the next point where MATLAB processes the queue, such as when there is a `drawnow`, `figure`, `uifigure`, `getframe`, `waitfor`, or `pause` command.
 - If the running callback contains one of those commands, then MATLAB stops the execution of the callback at that point and executes the interrupting callback. MATLAB resumes executing the running callback when the interrupting callback completes.
 - If the running callback does not contain one of those commands, then MATLAB finishes executing the callback without interruption.
- A value of 'off' blocks all interruption attempts. The `BusyAction` property of the object owning the interrupting callback determines if the interrupting callback is discarded or put into a queue.

Note Callback interruption and execution behave differently in these situations:

- If the interrupting callback is a `DeleteFcn`, `CloseRequestFcn` or `SizeChangedFcn` callback, then the interruption occurs regardless of the `Interruptible` property value.
- If the running callback is currently executing the `waitfor` function, then the interruption occurs regardless of the `Interruptible` property value.
- Timer objects execute according to schedule regardless of the `Interruptible` property value.

When an interruption occurs, MATLAB does not save the state of properties or the display. For example, the object returned by the `gca` or `gcf` command might change when another callback executes.

BusyAction — Callback queuing

'queue' (default) | 'cancel'

Callback queuing, specified as 'queue' or 'cancel'. The `BusyAction` property determines how MATLAB handles the execution of interrupting callbacks. There are two callback states to consider:

- The running callback is the currently executing callback.
- The interrupting callback is a callback that tries to interrupt the running callback.

Whenever MATLAB invokes a callback, that callback attempts to interrupt a running callback. The `Interruptible` property of the object owning the running callback determines if interruption is permitted. If interruption is not permitted, then the `BusyAction` property of the object owning the interrupting callback determines if it is discarded or put in the queue. These are possible values of the `BusyAction` property:

- 'queue' — Puts the interrupting callback in a queue to be processed after the running callback finishes execution.
- 'cancel' — Does not execute the interrupting callback.

BeingDeleted — Deletion status

on/off logical value

This property is read-only.

Deletion status, returned as an on/off logical value of type `matlab.lang.OnOffSwitchState`.

MATLAB sets the `BeingDeleted` property to 'on' when the `DeleteFcn` callback begins execution. The `BeingDeleted` property remains set to 'on' until the component object no longer exists.

Check the value of the `BeingDeleted` property to verify that the object is not about to be deleted before querying or modifying it.

Parent/Child

HandleVisibility — Visibility of object handle

'on' (default) | 'callback' | 'off'

Visibility of the object handle, specified as 'on', 'callback', or 'off'.

This property controls the visibility of the object in its parent's list of children. When an object is not visible in its parent's list of children, it is not returned by functions that obtain objects by searching the object hierarchy or querying properties. These functions include `get`, `findobj`, `clf`, and `close`. Objects are valid even if they are not visible. If you can access an object, you can set and get its properties, and pass it to any function that operates on objects.

HandleVisibility Value	Description
'on'	The object is always visible.
'callback'	The object is visible from within callbacks or functions invoked by callbacks, but not from within functions invoked from the command line. This option blocks access to the object at the command-line, but allows callback functions to access it.
'off'	The object is invisible at all times. This option is useful for preventing unintended changes to the UI by another function. Set the <code>HandleVisibility</code> to 'off' to temporarily hide the object during the execution of that function.

Parent — Parent container

Figure object (default) | Panel object | Tab object | ButtonGroup object | GridLayout object

Parent container, specified as a Figure object created using the `uifigure` function, or one of its child containers: `Tab`, `Panel`, `ButtonGroup`, or `GridLayout`. If no container is specified, MATLAB calls the `uifigure` function to create a new Figure object that serves as the parent container.

Identifiers

Type — Type of graphics object

'uiaeroaltimeter'

This property is read-only.

Type of graphics object, returned as `'uiaeroaltimeter'`.

Tag – Object identifier

`''` (default) | character vector | string scalar

Object identifier, specified as a character vector or string scalar. You can specify a unique `Tag` value to serve as an identifier for an object. When you need access to the object elsewhere in your code, you can use the `findobj` function to search for the object based on the `Tag` value.

UserData – User data

`[]` (default) | array

User data, specified as any MATLAB array. For example, you can specify a scalar, vector, matrix, cell array, character array, table, or structure. Use this property to store arbitrary data on an object.

If you are working in App Designer, create public or private properties in the app to share data instead of using the `UserData` property. For more information, see “Share Data Within App Designer Apps”.

See Also

`uiaeroaltimeter`

Topics

“Create and Configure Flight Instrument Component and an Animation Object” on page 2-49

“Display Flight Trajectory Data Using Flight Instruments and Flight Animation” on page 5-111

Introduced in R2018b

angle2dcm

Convert rotation angles to direction cosine matrix

Syntax

```
dcm = angle2dcm(rotationAng1,rotationAng2,rotationAng3)
dcm = angle2dcm( ____,rotationSequence)
```

Description

`dcm = angle2dcm(rotationAng1,rotationAng2,rotationAng3)` calculates the direction cosine matrix given three sets of rotation angles specifying yaw, pitch, and roll. The rotation used in this function is a passive transformation between two coordinate systems.

`dcm = angle2dcm(____, rotationSequence)` calculates the direction cosine matrix given three sets of rotation angles.

Examples

Direction Cosine Matrix from Angles

Calculate direction cosine matrix from rotation angles.

```
yaw = 0.7854;
pitch = 0.1;
roll = 0;
dcm = angle2dcm( yaw, pitch, roll )
```

dcm = 3×3

```
    0.7036    0.7036   -0.0998
   -0.7071    0.7071         0
    0.0706    0.0706    0.9950
```

Direction Cosine Matrix from Rotation Angle and Sequence

Calculate direction cosine matrix from rotation angles and rotation sequence.

```
yaw = [0.7854 0.5];
pitch = [0.1 0.3];
roll = [0 0.1];
dcm = angle2dcm( pitch, roll, yaw, 'YXZ' )
```

dcm =
dcm(:, :, 1) =

```
    0.7036    0.7071   -0.0706
```

```
-0.7036    0.7071    0.0706  
0.0998         0    0.9950
```

```
dcm(:, :, 2) =
```

```
0.8525    0.4770   -0.2136  
-0.4321    0.8732    0.2254  
0.2940   -0.0998    0.9506
```

Input Arguments

rotationAng1 — First rotation angles

m-by-1 array

First rotation angles, specified as an *m*-by-1 array, in rads.

Data Types: double | single

rotationAng2 — Second rotation angles

m-by-1 array

Second rotation angles, specified as an *m*-by-1 array, in rads.

Data Types: double | single

rotationAng3 — Third rotation angles

m-by-1 array

Third rotation angles, specified as an *m*-by-1 array, in rads.

Data Types: double | single

rotationSequence — Rotation sequence

'ZYX' (default) | 'ZYX' | 'YZX' | 'ZXY' | 'ZXZ' | 'YXZ' | 'YXY' | 'YZX' | 'YZY' | 'XYZ' | 'XZY' | 'YXY' | 'XZX'

Rotation sequence, specified as a scalar.

Data Types: char | string

Output Arguments

dcm — Direction cosine matrices

3-by-3-by-*m* matrix

Direction cosine matrices, specified as a 3-by-3-by-*m* matrix, where *m* is the number of direction cosine matrices.

See Also

angle2quat | dcm2angle | dcm2quat | quat2angle | quat2dcm

Introduced in R2006b

angle2quat

Convert rotation angles to quaternion

Syntax

```
quaternion = angle2quat(rotationAng1,rotationAng2,rotationAng3)
quaternion = angle2quat(rotationAng1,rotationAng2,rotationAng3,
rotationSequence)
```

Description

`quaternion = angle2quat(rotationAng1,rotationAng2,rotationAng3)` calculates the quaternion for three rotation angles. Aerospace Toolbox uses quaternions that are defined using the scalar-first convention. The rotation used in this function is a passive transformation between two coordinate systems.

`quaternion = angle2quat(rotationAng1,rotationAng2,rotationAng3,rotationSequence)` calculates the quaternion using a rotation sequence.

Examples

Determine Quaternion from Rotation Angles

Determine the quaternion from rotation angles:

```
yaw = 0.7854;
pitch = 0.1;
roll = 0;
q = angle2quat(yaw, pitch, roll)

q =
    0.9227    -0.0191    0.0462    0.3822
```

Determine Quaternion from Rotation Angles and Sequence

Determine the quaternion from rotation angles using the YXZ rotation sequence:

```
yaw = [0.7854 0.5];
pitch = [0.1 0.3];
roll = [0 0.1];
q = angle2quat(pitch, roll, yaw, 'YXZ')
```

```
q =  
    0.9227    0.0191    0.0462    0.3822  
    0.9587    0.0848    0.1324    0.2371
```

Input Arguments

rotationAng1 — First rotation angles

m-by-1 array

First rotation angles, specified as an *m*-by-1 array, in radians.

Data Types: double

rotationAng2 — Second rotation angles

m-by-1 array

Second rotation angles, specified as an *m*-by-1 array, in radians.

Data Types: double

rotationAng3 — Third rotation angles

m-by-1 array

Third rotation angles, specified as an *m*-by-1 array, in radians.

Data Types: double

rotationSequence — Rotation sequence

'ZYZ' (default) | 'ZYX' | 'ZXY' | 'ZXZ' | 'YXZ' | 'YXY' | 'YZX' | 'YZY' | 'XYZ' | 'XZY' | 'XYX' | 'XZX'

Rotation sequence, specified as:

- 'ZYZ'
- 'ZYX'
- 'ZXY'
- 'ZXZ'
- 'YXZ'
- 'YXY'
- 'YZX'
- 'YZY'
- 'XYZ'
- 'XZY'
- 'XYX'
- 'XZX'

where `rotationAng1` is z-axis rotation, `rotationAng2` is y-axis rotation, and `rotationAng3` is x-axis rotation.

Data Types: char | string

Output Arguments

quat — Converted quaternion

m-by-4 matrix

Converted quaternion, returned as an *m*-by-4 matrix containing *m* quaternions. `quat` has its scalar number as the first column.

See Also

`angle2dcm` | `dcm2angle` | `dcm2quat` | `quat2angle` | `quat2dcm`

Introduced in R2007b

angle2rod

Convert rotation angles to Euler-Rodrigues vector

Syntax

```
rod=angle2rod(R1,R2,R3)
rod=angle2rod(R1,R2,R3,S)
```

Description

`rod=angle2rod(R1,R2,R3)` function converts the rotation described by the three rotation angles, `R1`, `R2`, and `R3`, into an M -by-3 Euler-Rodrigues matrix, `rod`. The rotation used in this function is a passive transformation between two coordinate systems.

`rod=angle2rod(R1,R2,R3,S)` function converts the rotation described by the three rotation angles and a rotation sequence, `S`, into an M -by-3 Euler-Rodrigues array, `rod`, that contains the M Rodrigues vector.

Examples

Determine the Rodrigues Vector from One Rotation Angle

Determine the Rodrigues vector from rotation angles.

```
yaw = 0.7854;
pitch = 0.1;
roll = 0;
r = angle2rod(yaw,pitch,roll)

r =

    -0.0207    0.0500    0.4142
```

Determine Rodrigues Vectors from Multiple Rotation Angles

Determine the Rodrigues vectors from multiple rotation angles.

```
yaw = [0.7854 0.5];
pitch = [0.1 0.3];
roll = [0 0.1];
r = angle2rod(pitch,roll,yaw,'YXZ')

r =
```

```
0.0207    0.0500    0.4142
0.0885    0.1381    0.2473
```

Input Arguments

R1 — First rotation angle

M-by-1 array

First rotation angle, in radians, from which to determine Euler-Rodrigues vector. Values must be real.

Data Types: `double` | `single`

R2 — Second rotation angle

M-by-1 array

Second rotation angle, in radians, from which to determine Euler-Rodrigues vector. Values must be real.

Data Types: `double` | `single`

R3 — Third rotation angle

M-by-1 array

Third rotation angle, in radians, from which to determine Euler-Rodrigues vector. Values must be real.

Data Types: `double` | `single`

S — Rotation sequence

ZYX (default) | ZYZ | ZXY | ZXZ | YXZ | YXY | YZX | YZY | XYZ | XYX | XZY | XZX

Rotation sequence. For the default rotation sequence, ZYX, the rotation angle order is:

- R1 — z-axis rotation
- R2 — y-axis rotation
- R3 — x-axis rotation

Data Types: `char` | `string`

Output Arguments

rod — Euler-Rodrigues vector

3-element vector

Euler-Rodrigues vector determined from rotation angles.

Algorithms

An Euler-Rodrigues vector \vec{b} represents a rotation by integrating a direction cosine of a rotation axis with the tangent of half the rotation angle as follows:

$$\vec{b} = [b_x \ b_y \ b_z]$$

where:

$$b_x = \tan\left(\frac{1}{2}\theta\right)s_x,$$

$$b_y = \tan\left(\frac{1}{2}\theta\right)s_y,$$

$$b_z = \tan\left(\frac{1}{2}\theta\right)s_z$$

are the Rodrigues parameters. Vector \vec{s} represents a unit vector around which the rotation is performed. Due to the tangent, the rotation vector is indeterminate when the rotation angle equals $\pm\pi$ radians or ± 180 deg. Values can be negative or positive.

References

- [1] Dai, J.S. "Euler-Rodrigues formula variations, quaternion conjugation and intrinsic connections." *Mechanism and Machine Theory*, 92, 144-152. Elsevier, 2015.

See Also

dcm2rod | quat2rod | rod2angle | rod2dcm | rod2quat

Introduced in R2017a

ArtificialHorizon Properties

Control artificial horizon appearance and behavior

Description

Artificial horizons are components that represent an artificial horizon. Properties control the appearance and behavior of an artificial horizon. Use dot notation to refer to a particular object and property:

```
f = uifigure;
artificialhorizon = uiaerohorizon(f);
artificialhorizon.Value = [100 20];
```

The artificial horizon represents aircraft attitude relative to horizon and displays roll and pitch in degrees:

- Values for roll cannot exceed +/- 90 degrees.
- Values for pitch cannot exceed +/- 30 degrees.

If the values exceed the maximum values, the gauge maximum and minimum values do not change.

Changes in roll value affect the gauge semicircles and the ticks located on the black arc turn accordingly. Changes in pitch value affect the scales and the distribution of the semicircles.

Properties

Artificial Horizon

Pitch — Pitch

0 (default) | finite, real, and scalar numeric

Pitch value, specified as any finite and scalar numeric. The pitch value determines the movement of the aircraft around the transverse axis, in degrees.

Example: 10

Dependencies

Specifying this value changes the second element of the `Value` vector. Conversely, changing the second element of the `Value` vector changes the `Pitch` value.

Data Types: double

Roll — Roll

0 (default) | finite, real, and scalar numeric

Roll value, specified as any finite and scalar numeric. The roll value determines the rotation of the aircraft around the longitudinal axis, in degrees.

Example: 10

Dependencies

Specifying this value changes the first element of the `Value` vector. Conversely, changing the first element of the `Value` vector changes the `Roll` value.

Data Types: `double`

Value — Roll and pitch

`[0 0]` (default) | two-element vector of finite, real, and scalar numerics

Roll and pitch values, specified as a vector (`[Roll Pitch]`).

- The roll value determines the rotation of the aircraft around the longitudinal axis.
- The pitch value determines the movement of the aircraft around the transverse axis.

Example: `[100 -200]`

Dependencies

- Specifying the `Roll` value changes the first element of the `Value` vector. Conversely, changing the first element of the `Value` vector changes the `Roll` value.
- Specifying the `Pitch` value changes the second element of the `Value` vector. Conversely, changing the second element of the `Value` vector changes the `Pitch` value.

Data Types: `double`

Interactivity**Visible — Visibility of artificial horizon**

`'on'` (default) | on/off logical value

Visibility of the artificial horizon, specified as `'on'` or `'off'`, or as numeric or logical `1` (`true`) or `0` (`false`). A value of `'on'` is equivalent to `true`, and `'off'` is equivalent to `false`. Thus, you can use the value of this property as a logical value. The value is stored as an on/off logical value of type `matlab.lang.OnOffSwitchState`. The `Visible` property determines whether the artificial horizon, is displayed on the screen. If the `Visible` property is set to `'off'`, then the entire artificial horizon is hidden, but you can still specify and access its properties.

ContextMenu — Context menu

empty `GraphicsPlaceholder` array (default) | `ContextMenu` object

Context menu, specified as a `ContextMenu` object created using the `uicontextmenu` function. Use this property to display a context menu when you right-click on a component.

Enable — Operational state of artificial horizon

`'on'` (default) | on/off logical value

Operational state of artificial horizon, specified as `'on'` or `'off'`, or as numeric or logical `1` (`true`) or `0` (`false`). A value of `'on'` is equivalent to `true`, and `'off'` is equivalent to `false`. Thus, you can use the value of this property as a logical value. The value is stored as an on/off logical value of type `matlab.lang.OnOffSwitchState`.

- If you set this property to `'on'`, then the appearance of the artificial horizon indicates that the artificial horizon is operational.
- If you set this property to `'off'`, then the appearance of the artificial horizon appears dimmed, indicating that the artificial horizon is not operational.

Position**Position — Location and size of artificial horizon**

[100 100 120 120] (default) | [left bottom width height]

Location and size of the artificial horizon relative to the parent container, specified as the vector, [left bottom width height]. This table describes each element in the vector.

Element	Description
left	Distance from the inner left edge of the parent container to the outer left edge of an imaginary box surrounding the artificial horizon
bottom	Distance from the inner bottom edge of the parent container to the outer bottom edge of an imaginary box surrounding the artificial horizon
width	Distance between the right and left outer edges of the artificial horizon
height	Distance between the top and bottom outer edges of the artificial horizon

All measurements are in pixel units.

The **Position** values are relative to the drawable area of the parent container. The drawable area is the area inside the borders of the container and does not include the area occupied by decorations such as a menu bar or title.

Example: [200 120 120 120]

InnerPosition — Inner location and size of artificial horizon

[100 100 120 120] (default) | [left bottom width height]

Inner location and size of the artificial horizon, specified as [left bottom width height].

Position values are relative to the parent container. All measurements are in pixel units. This property value is identical to the **Position** property.

OuterPosition — Outer location and size of artificial horizon

[100 100 120 120]] (default) | [left bottom width height]

This property is read-only.

Outer location and size of the artificial horizon returned as [left bottom width height].

Position values are relative to the parent container. All measurements are in pixel units. This property value is identical to the **Position** property.

Layout — Layout options

empty `LayoutOptions` array (default) | `GridLayoutOptions` object

Layout options, specified as a `GridLayoutOptions` object. This property specifies options for components that are children of grid layout containers. If the component is not a child of a grid layout container (for example, it is a child of a figure or panel), then this property is empty and has no effect. However, if the component is a child of a grid layout container, you can place the component in the desired row and column of the grid by setting the `Row` and `Column` properties on the `GridLayoutOptions` object.

For example, this code places an artificial horizon in the third row and second column of its parent grid.

```
g = ui([4 3]);  
gauge = uiaerohorizon(g);  
gauge.Layout.Row = 3;  
gauge.Layout.Column = 2;
```

To make the artificial horizon span multiple rows or columns, specify the `Row` or `Column` property as a two-element vector. For example, this artificial horizon spans columns 2 through 3:

```
gauge.Layout.Column = [2 3];
```

Callbacks

CreateFcn — Creation function

' ' (default) | function handle | cell array | character vector

Object creation function, specified as one of these values:

- Function handle.
- Cell array in which the first element is a function handle. Subsequent elements in the cell array are the arguments to pass to the callback function.
- Character vector containing a valid MATLAB expression (not recommended). MATLAB evaluates this expression in the base workspace.

For more information about specifying a callback as a function handle, cell array, or character vector, see “Write Callbacks in App Designer”.

This property specifies a callback function to execute when MATLAB creates the object. MATLAB initializes all property values before executing the `CreateFcn` callback. If you do not specify the `CreateFcn` property, then MATLAB executes a default creation function.

Setting the `CreateFcn` property on an existing component has no effect.

If you specify this property as a function handle or cell array, you can access the object that is being created using the first argument of the callback function. Otherwise, use the `gcbo` function to access the object.

DeleteFcn — Deletion function

' ' (default) | function handle | cell array | character vector

Object deletion function, specified as one of these values:

- Function handle.
- Cell array in which the first element is a function handle. Subsequent elements in the cell array are the arguments to pass to the callback function.
- Character vector containing a valid MATLAB expression (not recommended). MATLAB evaluates this expression in the base workspace.

For more information about specifying a callback as a function handle, cell array, or character vector, see “Write Callbacks in App Designer”.

This property specifies a callback function to execute when MATLAB deletes the object. MATLAB executes the `DeleteFcn` callback before destroying the properties of the object. If you do not specify the `DeleteFcn` property, then MATLAB executes a default deletion function.

If you specify this property as a function handle or cell array, you can access the object that is being deleted using the first argument of the callback function. Otherwise, use the `gcbo` function to access the object.

Callback Execution Control

BusyAction — Callback queuing

'queue' (default) | 'cancel'

Callback queuing, specified as 'queue' or 'cancel'. The `BusyAction` property determines how MATLAB handles the execution of interrupting callbacks. There are two callback states to consider:

- The running callback is the currently executing callback.
- The interrupting callback is a callback that tries to interrupt the running callback.

Whenever MATLAB invokes a callback, that callback attempts to interrupt a running callback. The `Interruptible` property of the object owning the running callback determines if interruption is permitted. If interruption is not permitted, then the `BusyAction` property of the object owning the interrupting callback determines if it is discarded or put in the queue. These are possible values of the `BusyAction` property:

- 'queue' — Puts the interrupting callback in a queue to be processed after the running callback finishes execution.
- 'cancel' — Does not execute the interrupting callback.

BeingDeleted — Deletion status

on/off logical value

This property is read-only.

Deletion status, returned as an on/off logical value of type `matlab.lang.OnOffSwitchState`.

MATLAB sets the `BeingDeleted` property to 'on' when the `DeleteFcn` callback begins execution. The `BeingDeleted` property remains set to 'on' until the component object no longer exists.

Check the value of the `BeingDeleted` property to verify that the object is not about to be deleted before querying or modifying it.

Interruptible — Callback interruption

'on' (default) | on/off logical value

Callback interruption, specified as 'on' or 'off', or as numeric or logical 1 (true) or 0 (false). A value of 'on' is equivalent to `true`, and 'off' is equivalent to `false`. Thus, you can use the value of this property as a logical value. The value is stored as an on/off logical value of type `matlab.lang.OnOffSwitchState`.

This property determines if a running callback can be interrupted. There are two callback states to consider:

- The running callback is the currently executing callback.

- The interrupting callback is a callback that tries to interrupt the running callback.

Whenever MATLAB invokes a callback, that callback attempts to interrupt the running callback (if one exists). The `Interruptible` property of the object owning the running callback determines if interruption is allowed.

- A value of `'on'` allows other callbacks to interrupt the object's callbacks. The interruption occurs at the next point where MATLAB processes the queue, such as when there is a `drawnow`, `figure`, `uifigure`, `getframe`, `waitfor`, or `pause` command.
 - If the running callback contains one of those commands, then MATLAB stops the execution of the callback at that point and executes the interrupting callback. MATLAB resumes executing the running callback when the interrupting callback completes.
 - If the running callback does not contain one of those commands, then MATLAB finishes executing the callback without interruption.
- A value of `'off'` blocks all interruption attempts. The `BusyAction` property of the object owning the interrupting callback determines if the interrupting callback is discarded or put into a queue.

Note Callback interruption and execution behave differently in these situations:

- If the interrupting callback is a `DeleteFcn`, `CloseRequestFcn` or `SizeChangedFcn` callback, then the interruption occurs regardless of the `Interruptible` property value.
- If the running callback is currently executing the `waitfor` function, then the interruption occurs regardless of the `Interruptible` property value.
- Timer objects execute according to schedule regardless of the `Interruptible` property value.

When an interruption occurs, MATLAB does not save the state of properties or the display. For example, the object returned by the `gca` or `gcf` command might change when another callback executes.

Parent/Child

HandleVisibility – Visibility of object handle

`'on'` (default) | `'callback'` | `'off'`

Visibility of the object handle, specified as `'on'`, `'callback'`, or `'off'`.

This property controls the visibility of the object in its parent's list of children. When an object is not visible in its parent's list of children, it is not returned by functions that obtain objects by searching the object hierarchy or querying properties. These functions include `get`, `findobj`, `clf`, and `close`. Objects are valid even if they are not visible. If you can access an object, you can set and get its properties, and pass it to any function that operates on objects.

HandleVisibility Value	Description
<code>'on'</code>	The object is always visible.
<code>'callback'</code>	The object is visible from within callbacks or functions invoked by callbacks, but not from within functions invoked from the command line. This option blocks access to the object at the command-line, but allows callback functions to access it.

HandleVisibility Value	Description
'off'	The object is invisible at all times. This option is useful for preventing unintended changes to the UI by another function. Set the HandleVisibility to 'off' to temporarily hide the object during the execution of that function.

Parent – Parent container

Figure object (default) | Panel object | Tab object | ButtonGroup object | GridLayout object

Parent container, specified as a `Figure` object created using the `uifigure` function, or one of its child containers: `Tab`, `Panel`, `ButtonGroup`, or `GridLayout`. If no container is specified, MATLAB calls the `uifigure` function to create a new `Figure` object that serves as the parent container.

Identifiers**Type – Type of graphics object**

'uiaerohorizon'

This property is read-only.

Type of graphics object, returned as 'uiaerohorizon'.

Tag – Object identifier

' ' (default) | character vector | string scalar

Object identifier, specified as a character vector or string scalar. You can specify a unique `Tag` value to serve as an identifier for an object. When you need access to the object elsewhere in your code, you can use the `findobj` function to search for the object based on the `Tag` value.

UserData – User data

[] (default) | array

User data, specified as any MATLAB array. For example, you can specify a scalar, vector, matrix, cell array, character array, table, or structure. Use this property to store arbitrary data on an object.

If you are working in App Designer, create public or private properties in the app to share data instead of using the `UserData` property. For more information, see “Share Data Within App Designer Apps”.

See Also

uiaerohorizon

Topics

“Create and Configure Flight Instrument Component and an Animation Object” on page 2-49

“Display Flight Trajectory Data Using Flight Instruments and Flight Animation” on page 5-111

Introduced in R2018b

atmoscoesa

Use 1976 COESA model

Syntax

```
[T, a, P, Rho] = atmoscoesa(height, action)
```

Description

Committee on Extension to the Standard Atmosphere has the acronym COESA. `[T, a, P, Rho] = atmoscoesa(height, action)` implements the mathematical representation of the 1976 COESA United States standard lower atmospheric values. These values are absolute temperature, pressure, density, and speed of sound for the input geopotential altitude.

Below the geopotential altitude of 0 m (0 feet) and above the geopotential altitude of 84,852 m (approximately 278,386 feet), the function extrapolates values. It extrapolates temperature values linearly and pressure values logarithmically.

Input Arguments

height

Array of m -by-1 geopotential heights, in meters.

action

Action for out-of-range input. Specify one:

'Error'

'Warning' (default)

'None'

Output Arguments

T

Array of m -by-1 temperatures, in kelvin.

a

Array of m -by-1 speeds of sound, in meters per second. The function calculates speed of sound using a perfect gas relationship.

P

Array of m -by-1 pressures, in pascal.

Rho

Array of m -by-1 densities, in kilograms per meter cubed. The function calculates density using a perfect gas relationship.

Examples

Calculate the COESA model at 1000 m with warnings for out-of-range inputs:

```
[T, a, P, rho] = atmoscoesa(1000)
```

T =

```
281.6500
```

a =

```
336.4341
```

P =

```
8.9875e+004
```

rho =

```
1.1116
```

Calculate the COESA model at 1000, 11,000, and 20,000 m with errors for out-of-range inputs:

```
[T, a, P, rho] = atmoscoesa([1000 11000 20000], 'Error')
```

T =

```
281.6500 216.6500 216.6500
```

a =

```
336.4341 295.0696 295.0696
```

P =

```
1.0e+004 *
```

```
8.9875 2.2632 0.5475
```

rho =

```
1.1116 0.3639 0.0880
```

References

U.S. Standard Atmosphere, 1976, U.S. Government Printing Office, Washington, D.C.

See Also

atmoscira | atmosisa | atmoslapse | atmosnonstd | atmospalt

Introduced in R2006b

atmoscira

Use COSPAR International Reference Atmosphere 1986 model

Syntax

```
[T altitude zonalWind] = atmoscira(latitude, ctype, coord, mtype, month,
action)
```

Description

[*T altitude zonalWind*] = `atmoscira(latitude, ctype, coord, mtype, month, action)` implements the mathematical representation of the Committee on Space Research (COSPAR) International Reference Atmosphere (CIRA) from 1986 model. The CIRA 1986 model provides a mean climatology. The mean climatology consists of temperature, zonal wind, and geopotential height or pressure. It encompasses nearly pole-to-pole coverage (80 degrees S to 80 degrees N) for 0 km to 120 km. This provision also encompasses the troposphere, middle atmosphere, and lower thermosphere. Use this mathematical representation as a function of pressure or geopotential height.

This function uses a corrected version of the CIRA data files provided by J. Barnett in July 1990 in ASCII format.

This function has the limitations of the CIRA 1986 model and limits the values for the CIRA 1986 model.

The CIRA 1986 model limits values to the regions of 80 degrees S to 80 degrees N on Earth. It also limits geopotential heights from 0 km to 120 km. In each monthly mean data set, the model omits values at 80 degrees S for 101,300 pascal or 0 m. It omits these values because these levels are within the Antarctic land mass. For zonal mean pressure in constant altitude coordinates, pressure data is not available below 20 km. Therefore, this value is the bottom level of the CIRA climatology.

Input Arguments

latitude

Array of *m* geodetic latitudes, in degrees, where north latitude is positive and south latitude is negative.

ctype

Representation of coordinate type of data type string. Specify:

'Pressure'	Pressure in pascal
'GPHeight'	Geopotential height in meters

coord

Depending on the value of `ctype`, this argument specifies one of the following arrays:

m Pressures in pascal
m Geopotential height in meters

mtype

Mean value type of data type string:

'Monthly' (default) Monthly values.
 'Annual' Annual values. Valid when *ctype* has a value of 'Pressure'.

month

Scalar value that selects the month in which the model takes the mean values. This argument applies only when *mtype* has a value of 'Monthly'.

1 (default)	January
2	February
3	March
4	April
5	May
6	June
7	July
8	August
9	September
10	October
11	November
12	December

action

Action for out-of-range input, of data type string. Specify one:

'Error'
 'Warning' (default)
 'None'

Output Arguments

T

Array of temperatures:

If *m* is 'Monthly' Array of *m* temperatures, in kelvin

If *mtype* is 'Annual'

Array of *m*-by-7 values:

- Annual mean temperature in kelvin
- Annual temperature cycle amplitude in kelvin
- Annual temperature cycle phase in month of maximum
- Semiannual temperature cycle amplitude in kelvin
- Semiannual temperature cycle phase in month of maximum
- Terannual temperature cycle amplitude in kelvin
- Terannual temperature cycle phase in month of maximum

altitude

If *mtype* is 'Monthly', an array of *m* geopotential heights or *m* air pressures:

If *ctype* is 'Pressure'

Array *m* geopotential heights

If *ctype* is 'GPHeight'

Array *m* air pressure

If *mtype* is 'Annual', an array of *m*-by-7 values for geopotential heights. The function defines this array only for the northern hemisphere (*latitude* is greater than 0).

- Annual mean geopotential heights in meters
- Annual geopotential heights cycle amplitude in meters
- Annual geopotential heights cycle phase in month of maximum
- Semiannual geopotential heights cycle amplitude in meters
- Semiannual geopotential heights cycle phase in month of maximum
- Terannual geopotential heights cycle amplitude in meters
- Terannual geopotential heights cycle phase in month of maximum

zonalWind

Array of zonal winds:

If *mtype* is 'Monthly'

Array in meters per second.

If *mtype* is 'Annual'

Array of *m*-by-7 values:

- Annual mean zonal winds in meters per second
- Annual zonal winds cycle amplitude in meters per second
- Annual zonal winds cycle phase in month of maximum
- Semiannual zonal winds cycle amplitude in meters per second
- Semiannual zonal winds cycle phase in month of maximum
- Terannual zonal winds cycle amplitude in meters per second
- Terannual zonal winds cycle phase in month of maximum

Examples

Using the CIRA 1986 model at 45 degrees latitude and 101,300 pascal for January with out-of-range actions generating warnings, calculate the mean monthly values. Calculate values for temperature (T), geopotential height (alt), and zonal wind ($zwind$).

```
[T, alt, zwind] = atmoscira( 45, 'Pressure', 101300 )
T =
    280.6000
alt =
    -18
zwind =
    3.3000
```

Using the CIRA 1986 model at 45 degrees latitude and 20,000 m for October with out-of-range actions generating warnings, calculate the mean monthly values. Calculate values for temperature (T), pressure ($pres$), and zonal wind ($zwind$).

```
[T, pres, zwind] = atmoscira( 45, 'GPHeight', 20000, 'Monthly', 10)
T =
    215.8500
pres =
    5.5227e+003
zwind =
    9.5000
```

Use the CIRA 1986 model at 45 and -30 degrees latitude and 20,000 m for October with out-of-range actions generating errors. Calculate values for temperature (T), pressure ($pres$), and zonal wind ($zwind$).

```
[T, pres, zwind] = atmoscira( [45 -30], 'GPHeight', 20000, 10, 'error')
T =
    215.8500    213.9000
pres =
    1.0e+003 *
    5.5227    5.6550
zwind =
    9.5000    4.3000
```

For September, with out-of-range actions generating warnings, use the CIRA 1986 model at 45 degrees latitude and -30 degrees latitude. Also use the model at 2000 pascal and 101,300 pascal. Calculate mean monthly values for temperature (T), geopotential height (alt), and zonal wind ($zwind$).

```
[T, alt, zwind] = atmoscira( [45 -30], 'Pressure', [2000 101300], 9)
T =
    223.5395    290.9000
alt =
    1.0e+004 *
    2.6692    0.0058
zwind =
    0.6300    -1.1000
```

Using the CIRA 1986 model at 45 degrees latitude and 2000 pascal with out-of-range actions generating warnings, calculate annual values. Calculate values for temperature (T), geopotential height (alt), and zonal wind ($zwind$).

```
[T, alt, zwind] = atmoscira( 45, 'Pressure', 2000, 'Annual' )
T =
    221.9596    5.0998    6.5300    1.9499    1.3000    1.0499    1.3000
alt =
    1.0e+004 *
    2.6465    0.0417    0.0007    0.0087    0.0001    0.0015    0.0002
```

```
zwind =  
  4.6099  14.7496  0.6000  1.6499  4.6000  0.5300  1.4000
```

References

Fleming, E. L., Chandra, S., Shoeberl, M. R., Barnett, J. J., *Monthly Mean Global Climatology of Temperature, Wind, Geopotential Height and Pressure for 0-120 km*, NASA TM100697, February 1988

<https://ccmc.gsfc.nasa.gov/modelweb/atmos/cospar1.html>

See Also

[atmoscoesa](#) | [atmosisa](#) | [atmoslapse](#) | [atmosnonstd](#) | [atmosnrlmsise00](#) | [atmospalt](#)

Introduced in R2007b

atmoshwm

Implement horizontal wind model

Syntax

```
wind = atmoshwm(latitude,longitude,altitude)
```

```
wind = atmoshwm(latitude,longitude,altitude,Name,Value)
```

Description

`wind = atmoshwm(latitude,longitude,altitude)` implements the U.S. Naval Research Laboratory Horizontal Wind Model (HWM™) routine to calculate the meridional and zonal components of the wind for one or more sets of geophysical data: `latitude`, `longitude`, and `altitude`.

`wind = atmoshwm(latitude,longitude,altitude,Name,Value)` uses additional options specified by one or more `Name,Value` pair arguments.

Examples

Calculate the Total Horizontal Wind Model

Calculate the total horizontal wind model for a latitude of 45 degrees south, longitude of 85 degrees west, and altitude of 25,000 m above mean sea level (msl). The date is the 150th day of the year, at 11 am UTC, using an Ap index of 80. The horizontal model version is 14.

```
w = atmoshwm(-45,-85,25000,'day',150,'seconds',39600,'apindex',80,'model','total','version','14')
```

```
w =
```

```
3.2874 25.8735
```

Calculate the Quiet Horizontal Wind Model

Calculate the quiet horizontal wind model for a latitude of 50 degrees north, two altitudes of 100,000 m and 150,000 m above msl, and a longitude of 20 degrees west. The date is midnight UTC of January 30. The default horizontal model version is 14.

```
w = atmoshwm([50;50],[-20;-20],[100000;150000],'day',[30;30])
```

```
w =
```

```
-42.9350  -40.3693
 29.1106   0.6253
```

Calculate a Disturbed Horizontal Wind Model

Calculate the disturbed horizontal wind model for an altitude of 150,000 m above msl at latitude 70 degrees north, longitude 65 degrees west. The date is midnight UTC of June 15. The default horizontal model version is 14.

```
dw = atmoshwm(70, -65, 150000, 'day', 166, 'model', 'disturbance')
```

```
dw =
    1.7954   -1.7130
```

Input Arguments

latitude — Geodetic latitude

scalar | *M*-by-1 array

Geodetic latitudes, in degrees, specified as a scalar or *M*-by-1 array, where *M* is one or more sets of geophysical data.

Example: -45

Data Types: double

longitude — Geodetic longitude

scalar | *M*-by-1 array

Geodetic longitudes, in degrees, specified as a scalar or *M*-by-1 array, where *M* is one or more sets of geophysical data.

Example: -85

Data Types: double

altitude — Geopotential height

scalar | *M*-by-1 array

Geopotential heights, in meters, within the range of 0 to 500 km, specified as a scalar or *M*-by-1 array. *M* is one or more sets of geophysical data.

Example: 25000

Data Types: double

Name-Value Pair Arguments

Specify optional comma-separated pairs of *Name*, *Value* arguments. *Name* is the argument name and *Value* is the corresponding value. *Name* must appear inside quotes. You can specify several name and value pair arguments in any order as *Name1*, *Value1*, ..., *NameN*, *ValueN*.

Example: 'apindex', 80, 'model', 'total' specifies that the total horizontal wind model be calculated for an Ap index of 80.

apindex — Ap index

M-by-1 array of zeroes (default) | scalar | *M*-by-1 array

Ap index for the Universal Coordinated Time (UTC) at which `atmoshwm` evaluates the model, specified as an M -by-1 array of zeroes, a scalar, or an M -by-1 array. M is one or more sets of geophysical data. Select the index from the NOAA National Geophysical Data Center, which contains three-hour interval geomagnetic disturbance index values. If the Ap index value is greater than zero, the model evaluation accounts for magnetic effects.

Specify the Ap index as a value from 0 through 400. Specify an Ap index value for only the disturbance or total wind model type.

Data Types: double

day — Day of year

M -by-1 array of ones (default) | scalar | M -by-1 array

Day of year in UTC. Specify the day as a value from 1 through 366 (for a leap year), specified as an M -by-1 array of zeroes, a scalar, or an M -by-1 array. M is one or more sets of geophysical data.

Data Types: double

seconds — Elapsed seconds

M -by-1 array of zeroes (default) | scalar | M -by-1 array

Elapsed seconds since midnight for the selected day, in UTC, specified as specified as an M -by-1 array of zeroes, a scalar, or an M -by-1 array. M is one or more sets of geophysical data.

Specify the seconds as a value from 0 through 86,400.

Data Types: double

model — Horizontal wind model type

'quiet' (default) | 'disturbance' | 'total'

Horizontal wind model type for which to calculate the wind components. This setting applies to all the sets of geophysical data in M .

- 'quiet'

Calculates the horizontal wind model without the magnetic disturbances. Quiet model types do not account for Ap index values. For this model type, do not specify an Ap index value when using this model type.

- 'disturbance'

Calculates the effect of only magnetic disturbances in the wind. For this model type, specify Ap index values greater than or equal to zero.

- 'total'

Calculates the combined effect of the quiet and magnetic disturbances. for this model type, specify Ap index values greater than or equal to zero.

Data Types: char | string

action — Function behavior

'Error' (default) | 'None' | 'Warning'

Function behavior when inputs are out of range, specified as one of these values. This type applies to all the sets of geophysical data in M .

Value	Description
'None'	No action.
'Warning'	Warning in the MATLAB Command Window, model simulation continues.
'Error'	MATLAB returns an exception, model simulation stops.

Data Types: char | string

version — Horizontal wind model version

'14' (default) | '07'

Implements specified horizontal wind model type.

- '14'
Horizontal Wind Model 14.
- '07'
Horizontal Wind Model 07.

Data Types: char | string

Output Arguments

wind — Meridional and zonal wind components

M-by-2 array

Meridional and zonal wind components of the horizontal wind model, returned as an *M*-by-2 array, in m/s.

See Also

atmoscira | atmoscoesa | atmosnr | msise00

External Websites

NOAA National Geophysical Data Center

An empirical model of the Earth's horizontal wind fields: HWM07

An update to the Horizontal Wind Model (HWM): The quiet time thermosphere

Introduced in R2016b

atmosisa

Use International Standard Atmosphere model

Syntax

```
[T, a, P, rho] = atmosisa(height)
```

Description

`[T, a, P, rho] = atmosisa(height)` implements the mathematical representation of the International Standard Atmosphere values for ambient temperature, pressure, density, and speed of sound for the input geopotential altitude.

This function assumes that temperature and pressure values are held constant for both:

- Below the geopotential altitude of 0 km
- Above the geopotential altitude of the tropopause (at 20 km)

Examples

Calculate International Standard Atmosphere at One Height

Calculate the International Standard Atmosphere at 1000 m.

```
[T, a, P, rho] = atmosisa(1000)
```

```
T = 281.6500
```

```
a = 336.4341
```

```
P = 8.9875e+04
```

```
rho = 1.1116
```

Calculate International Standard Atmosphere at Multiple Heights

Calculate the International Standard Atmosphere at 1000, 11,000, and 20,000 m.

```
[T, a, P, rho] = atmosisa([1000 11000 20000])
```

```
T = 1×3
```

```
281.6500 216.6500 216.6500
```

```
a = 1×3
```

```
336.4341 295.0696 295.0696
```

```
P = 1×3  
104 ×  
      8.9875    2.2632    0.5475
```

```
rho = 1×3  
      1.1116    0.3639    0.0880
```

Input Arguments

height — Geopotential heights

m-by-m array

Geopotential heights, specified as an *m-by-m* array.

Data Types: `double`

Output Arguments

T — Temperatures

m-element array

Temperatures, returned as an *m*-element array, in kelvin.

a — Speeds of sound

m-element array

Speeds of sound, returned as an *m*-element array, in meters per second. The function calculates speed of sound using a perfect gas relationship.

P — Pressures

m-element array

Pressures, returned as an *m*-element array, in pascal.

rho — Densities

m-element array

Densities, returned as an *m*-element array, in kilograms per meter cubed. The function calculates density using a perfect gas relationship.

References

[1] *U.S. Standard Atmosphere, 1976*. U.S. Government Printing Office, Washington, D.C.

See Also

`atmoscira` | `atmoscoesa` | `atmoslapse` | `atmosnonstd` | `atmospalt`

Introduced in R2006b

atmoslapse

Use Lapse Rate Atmosphere model

Syntax

```
[T, a, P, rho] = atmoslapse(height, g, heatRatio, characteristicGasConstant,
lapseRate, heightTroposphere, heightTropopause, density0, pressure0,
temperature0)
```

```
[T, a, P, rho] = atmoslapse(height, g, heatRatio, characteristicGasConstant,
lapseRate, heightTroposphere, heightTropopause, density0, pressure0,
temperature0, height0)
```

Description

`[T, a, P, rho] = atmoslapse(height, g, heatRatio, characteristicGasConstant, lapseRate, heightTroposphere, heightTropopause, density0, pressure0, temperature0)` implements the mathematical representation of the lapse rate atmospheric equations for ambient temperature, pressure, density, and speed of sound for the input geopotential altitude. To customize this atmospheric model, specify the atmospheric properties in the function input.

The function holds temperature and pressure values below the geopotential altitude of 0 km and above the geopotential altitude of the tropopause. The function calculates the density and speed of sound using a perfect gas relationship.

`[T, a, P, rho] = atmoslapse(height, g, heatRatio, characteristicGasConstant, lapseRate, heightTroposphere, heightTropopause, density0, pressure0, temperature0, height0)` indicates that the values for ambient temperature, pressure, density, and speed of sound are for below mean sea level geopotential altitudes.

The function holds temperature and pressure values below the geopotential altitude of `height0` and above the geopotential altitude of the tropopause. The function calculates the density and speed of sound using a perfect gas relationship.

Input Arguments

height

Array of m -by- n geopotential heights, in meters.

g

Scalar of acceleration due to gravity, in meters per second squared.

heatRatio

Scalar of specific heat ratio.

characteristicGasConstant

Scalar of characteristic gas constant, in joule per kilogram-kelvin.

lapseRate

Scalar of lapse rate, in kelvin per meter.

heightTroposphere

Scalar of height of troposphere, in meters.

heightTropopause

Scalar of height of tropopause, in meters.

density0

Scalar of air density at mean sea level, in kilograms per meter cubed.

pressure0

Scalar of static pressure at mean sea level, in pascal.

temperature0

Scalar of absolute temperature at mean sea level, in kelvin.

height0

Scalar of minimum sea level altitude, in meters. Default height value is 0.

Output Arguments**T**

Array of m -by-1 temperatures, in kelvin.

a

Array of m -by-1 speeds of sound, in meters per second. The function calculates speed of sound using a perfect gas relationship.

P

Array of m -by-1 pressures, in pascal.

rho

Array of m -by-1 densities, in kilograms per meter cubed. The function calculates density using a perfect gas relationship.

Examples

Calculate the atmosphere at 1000 m with the International Standard Atmosphere input values:

```
[T, a, P, rho] = atmoslapse(1000, 9.80665, 1.4, 287.0531, 0.0065, ...  
    11000, 20000, 1.225, 101325, 288.15 )
```

T =

281.6500

a =

336.4341

P =

8.9875e+004

rho =

1.1116

References

U.S. Standard Atmosphere, 1976, U.S. Government Printing Office, Washington, D.C.

See Also

[atmoscira](#) | [atmoscoesa](#) | [atmosisa](#) | [atmosnonstd](#) | [atmospalt](#)

Introduced in R2006b

atmosnonstd

Use climatic data from MIL-STD-210 or MIL-HDBK-310

Syntax

$[T, a, P, rho] = \text{atmosnonstd}(\text{height}, \text{atmosphericType}, \text{extremeParameter}, \text{frequency}, \text{extremeAltitude}, \text{action}, \text{specification})$

Description

$[T, a, P, rho] = \text{atmosnonstd}(\text{height}, \text{atmosphericType}, \text{extremeParameter}, \text{frequency}, \text{extremeAltitude}, \text{action}, \text{specification})$ implements a portion of the climatic data of the MIL-STD-210C or MIL-HDBK-310 worldwide air environment to 80 km geometric (or approximately 262,000 feet geometric). This implementation provides absolute temperature, pressure, density, and speed of sound for the input geopotential altitude.

This function holds all values below the geometric altitude of 0 m (0 feet) and above the geometric altitude of 80,000 m (approximately 262,000 feet). The envelope atmospheric model has exceptions where values are held below the geometric altitude of 1 km (approximately 3281 feet). It also has exceptions above the geometric altitude of 30,000 m (approximately 98,425 feet). These exceptions are due to lack of data in MIL-STD-210 or MIL-HDBK-310 for these conditions.

In general, this function interpolates temperature values linearly and density values logarithmically. It calculates pressure and speed of sound using a perfect gas relationship. The envelope atmospheric model has exceptions where the extreme value is the only value provided as an output. In these cases, the function interpolates pressure logarithmically. These envelope atmospheric model exceptions apply to all cases of high and low pressure, high and low temperature, and high and low density. These exceptions exclude the extreme values and 1% frequency of occurrence. These exceptions are due to lack of data in MIL-STD-210 or MIL-HDBK-310 for these conditions.

A limitation is that MIL-STD-210 and MIL-HDBK-310 exclude from consideration climatic data for the region south of 60 degrees S latitude.

This function uses the metric version of data from the MIL-STD-210 or MIL-HDBK-310 specifications. A limitation is some inconsistent data between the metric and English data. Locations where these inconsistencies occur are within the envelope data for low density, low temperature, high temperature, low pressure, and high pressure. The most noticeable differences occur in the following values:

- For low density envelope data with 5% frequency, the density values in metric units are inconsistent at 4 km and 18 km. In addition, the density values in English units are inconsistent at 14 km.
- For low density envelope data with 10% frequency, the density values in metric units are inconsistent at 18 km. In addition, the density values in English units are inconsistent at 14 km.
- For low density envelope data with 20% frequency, the density values in English units are inconsistent at 14 km.
- For high-pressure envelope data with 10% frequency, the pressure values at 8 km are inconsistent.

Input Arguments

height

Array of m -by-1 geopotential heights, in meters.

atmosphericType

Representation of 'Profile' or 'Envelope' for the atmospheric data:

'Profile'	Is the realistic atmospheric profiles associated with extremes at specified altitudes. Use 'Profile' for simulation of vehicles vertically traversing the atmosphere, or when you need the total influence of the atmosphere.
'Envelope'	Uses extreme atmospheric values at each altitude. Use 'Envelope' for vehicles traversing the atmosphere horizontally, without much change in altitude.

extremeParameter

Atmospheric parameter that is the extreme value. Atmospheric parameters that you can specify are:

'High temperature'
 'Low temperature'
 'High density'
 'Low density'
 'High pressure', available only if *atmosphericType* is 'Envelope'
 'Low pressure', available only if *atmosphericType* is 'Envelope'

frequency

Percent of time that extreme values would occur. When using *atmosphericType* of 'Envelope' and *frequency* of '5%', '10%', and '20%', only the *extreme** parameter that you specify (temperature, density, or pressure) has a valid output. All other parameter outputs are zero.

'Extreme values', available only if *atmosphericType* is 'Envelope'
 '1%'
 '5%', available only if *atmosphericType* is 'Envelope'
 '10%'
 '20%', available only if *atmosphericType* is 'Envelope'

extremeAltitude

Scalar value, in kilometers, selecting geometric altitude at which the extreme values occur. *extremeAltitude* applies only when *atmosphericType* is 'Profile'.

5	16404 ft
10	32808 ft
20	65617 ft
30	98425 ft
40	131234 ft

action

Action for out-of-range input:

'Error'
'Warning' (default)
'None'

specification

Atmosphere model:

'210c'	MIL-STD-210C
'310'	MIL-HDBK-310 (default)

Output Arguments

T

Array of m -by-1 temperatures, in kelvin. This function interpolates temperature values linearly.

a

Array of m -by-1 speeds of sound, in meters per second. This function calculates speed of sound using a perfect gas relationship.

P

Array of m -by-1 pressures, in pascal. This function calculates pressure using a perfect gas relationship.

rho

Array of m -by-1 densities, in kilograms per meter cubed. This function interpolates density values logarithmically.

Examples

Calculate the nonstandard atmosphere profile. Use high density occurring 1% of the time at 5 km from MIL-HDBK-310 at 1000 m with warnings for out-of-range inputs:

```
[T, a, P, rho] = atmosnonstd( 1000, 'Profile', 'High density', '1%', 5 )
```

T =

```
248.1455
```

a =

```
315.7900
```

P =

```
8.9893e+004
```

rho =

```
1.2620
```

Calculate the nonstandard atmosphere envelope with high pressure. Assume that high pressure occurs 20% of the time from MIL-STD-210C at 1000, 11,000, and 20,000 m with errors for out-of-range inputs:


```
[T, a, P, rho] = atmosnonstd([1000 11000 20000], 'Envelope', ...  
                             'High pressure', '20%', 'Error', '210c' )
```

T =

0 0 0

a =

0 0 0

P =

1.0e+004 *
9.1598 2.5309 0.6129

rho =

0 0 0

References

Global Climatic Data for Developing Military Products (MIL-STD-210C), 9 January 1987, Department of Defense, Washington, D.C.

Global Climatic Data for Developing Military Products (MIL-HDBK-310), 23 June 1997, Department of Defense, Washington, D.C.

See Also

atmoscira | atmoscoesa | atmosisa | atmoslapse | atmospalt

Introduced in R2006b

atmosnrlmsise00

Implement mathematical representation of 2001 United States Naval Research Laboratory Mass Spectrometer and Incoherent Scatter Radar Exosphere

Syntax

$[T \text{ rho}] = \text{atmosnrlmsise00}(\text{altitude}, \text{latitude}, \text{longitude}, \text{year}, \text{dayOfYear}, \text{UTseconds})$

$[T \text{ rho}] = \text{atmosnrlmsise00}(\text{altitude}, \text{latitude}, \text{longitude}, \text{year}, \text{dayOfYear}, \text{UTseconds}, \text{localApparentSolarTime})$

$[T \text{ rho}] = \text{atmosnrlmsise00}(\text{altitude}, \text{latitude}, \text{longitude}, \text{year}, \text{dayOfYear}, \text{UTseconds}, \text{f107Average}, \text{f107Daily}, \text{magneticIndex})$

$[T \text{ rho}] = \text{atmosnrlmsise00}(\text{altitude}, \text{latitude}, \text{longitude}, \text{year}, \text{dayOfYear}, \text{UTseconds}, \text{flags})$

$[T \text{ rho}] = \text{atmosnrlmsise00}(\text{altitude}, \text{latitude}, \text{longitude}, \text{year}, \text{dayOfYear}, \text{UTseconds}, \text{otype})$

$[T \text{ rho}] = \text{atmosnrlmsise00}(\text{altitude}, \text{latitude}, \text{longitude}, \text{year}, \text{dayOfYear}, \text{UTseconds}, \text{action})$

Description

$[T \text{ rho}] = \text{atmosnrlmsise00}(\text{altitude}, \text{latitude}, \text{longitude}, \text{year}, \text{dayOfYear}, \text{UTseconds})$ implements the mathematical representation of the 2001 United States Naval Research Laboratory Mass Spectrometer and Incoherent Scatter Radar Exosphere (NRLMSISE-00) of the MSIS[®] class model. NRLMSISE-00 calculates the neutral atmosphere empirical model from the surface to lower exosphere (0 m to 1,000,000 m). Optionally, it performs this calculation including contributions from anomalous oxygen that can affect satellite drag above 500,000 m.

$[T \text{ rho}] = \text{atmosnrlmsise00}(\text{altitude}, \text{latitude}, \text{longitude}, \text{year}, \text{dayOfYear}, \text{UTseconds}, \text{localApparentSolarTime})$ specifies an array of m local apparent solar time (hours).

$[T \text{ rho}] = \text{atmosnrlmsise00}(\text{altitude}, \text{latitude}, \text{longitude}, \text{year}, \text{dayOfYear}, \text{UTseconds}, \text{f107Average}, \text{f107Daily}, \text{magneticIndex})$ specifies arrays of m 81 day average of F10.7 flux (centered on doy), m -by-1 daily F10.7 flux for previous day, and m -by-7 of magnetic index information.

$[T \text{ rho}] = \text{atmosnrlmsise00}(\text{altitude}, \text{latitude}, \text{longitude}, \text{year}, \text{dayOfYear}, \text{UTseconds}, \text{flags})$ specifies an array of 23 to enable or disable particular variations for the outputs.

$[T \text{ rho}] = \text{atmosnrlmsise00}(\text{altitude}, \text{latitude}, \text{longitude}, \text{year}, \text{dayOfYear}, \text{UTseconds}, \text{otype})$ specifies a character vector or string for total mass density output.

$[T \text{ rho}] = \text{atmosnrlmsise00}(\text{altitude}, \text{latitude}, \text{longitude}, \text{year}, \text{dayOfYear}, \text{UTseconds}, \text{action})$ specifies out-of-range input action.

This function has the limitations of the NRLMSISE-00 model. For more information, see the NRLMSISE-00 model documentation.

The NRLMSISE-00 model uses *UTseconds*, *localApparentSolarTime*, and *longitude* independently. These arguments are not of equal importance for every situation. For the most physically realistic calculation, choose these three variables to be consistent by default:

$$\text{localApparentSolarTime} = \text{UTseconds}/3600 + \text{longitude}/15$$

If available, you can include departures from this equation for *localApparentSolarTime*, but they are of minor importance.

Input Arguments

action

Action for out-of-range input. Specify one:

'Error'

'Warning' (default)

'None'

altitude

Array of *m*-by-1 altitudes, in meters.

dayOfYear

Array *m*-by-1 day of year.

f107Average

Array of *m*-by-1 81 day average of F10.7 flux (centered on day of year (*dayOfYear*)). If you specify *f107Average*, you must also specify *f107Daily* and *magneticIndex*. The effects of *f107Average* are not large or established below 80,000 m; therefore, the default value is 150.

These *f107Average* values correspond to the 10.7 cm radio flux at the actual distance of the Earth from the Sun. The *f107Average* values do not correspond to the radio flux at 1 AU. The following site provides both classes of values: <ftp://ftp.ngdc.noaa.gov/STP/space-weather/solar-data/solar-features/solar-radio/noontime-flux/penticton/>

See the limitations in "Description" on page 4-162 for more information.

f107Daily

Array of *m*-by-1 daily F10.7 flux for previous day. If you specify *f107Daily*, you must also specify *f107Average* and *magneticIndex*. The effects of *f107Daily* are not large or established below 80,000 m; therefore, the default value is 150.

These *f107Daily* values correspond to the 10.7 cm radio flux at the actual distance of the Earth from the Sun. The *f107Daily* values do not correspond to the radio flux at 1 AU. The following site provides both classes of values: <ftp://ftp.ngdc.noaa.gov/STP/space-weather/solar-data/solar-features/solar-radio/noontime-flux/penticton/>

See the limitations in "Description" on page 4-162 for more information.

flags

Array of 23 to enable or disable particular variations for the outputs. If *flags* array length, *m*, is 23 and you have not specified all available inputs, this function assumes that *flags* is set.

The flags, associated with the *flags* input, enable or disable particular variations for the outputs:

Field	Description
Flags(1)	F10.7 effect on mean
Flags(2)	Independent of time
Flags(3)	Symmetrical annual
Flags(4)	Symmetrical semiannual
Flags(5)	Asymmetrical annual
Flags(6)	Asymmetrical semiannual
Flags(7)	Diurnal
Flags(8)	Semidiurnal
Flags(9)	Daily AP. If you set this field to -1, the function uses the entire matrix of magnetic index information (APH) instead of APH(:,1).
Flags(10)	All UT, longitudinal effects
Flags(11)	Longitudinal
Flags(12)	UT and mixed UT, longitudinal
Flags(13)	Mixed AP, UT, longitudinal
Flags(14)	Terdiurnal
Flags(15)	Departures from diffusive equilibrium
Flags(16)	All exospheric temperature variations
Flags(17)	All variations from 120,000 meter temperature (TLB)
Flags(18)	All lower thermosphere (TN1) temperature variations
Flags(19)	All 120,000 meter gradient (S) variations
Flags(20)	All upper stratosphere (TN2) temperature variations
Flags(21)	All variations from 120,000 meter values (ZLB)
Flags(22)	All lower mesosphere temperature (TN3) variations
Flags(23)	Turbopause scale height variations

latitude

Array of *m*-by-1 geodetic latitudes, in degrees.

longitude

Array of *m*-by-1 longitudes, in degrees.

localApparentSolarTime

Array of *m*-by-1 local apparent solar time (hours). To obtain a physically realistic value, the function sets *localApparentSolarTime* to $(\text{sec}/3600 + \text{lon}/15)$ by default. See "Description" on page 4-162 for more information.

magneticIndex

An array of m -by-7 of magnetic index information. If you specify *magneticIndex*, you must also specify *f107Average* and *f107Daily*. This information consists of:

Daily magnetic index (AP)

3 hour AP for current time

3 hour AP for 3 hours before current time

3 hour AP for 6 hours before current time

3 hour AP for 9 hours before current time

Average of eight 3 hour AP indices from 12 to 33 hours before current time

Average of eight 3 hour AP indices from 36 to 57 hours before current time

The effects of daily magnetic index are not large or established below 80,000 m. As a result, the function sets the default value to 4. See the limitations in "Description" on page 4-162 for more information.

otype

Total mass density output:

'Oxygen ' Total mass density outputs include anomalous oxygen number density.

'NoOxygen ' Total mass density outputs do not include anomalous oxygen number density.

UTseconds

Array of m -by-1 seconds in day in universal time (UT)

year

This function ignores the value of *year*.

Output Arguments**T**

Array of N -by-2 values of temperature, in kelvin. The first column is exospheric temperature, in kelvin. The second column is temperature at altitude, in kelvin.

rho

An array of N -by-9 values of densities (kg/m^3 or $1/\text{m}^3$) in selected density units. The column order is:

Density of He, in $1/\text{m}^3$

Density of O, in $1/\text{m}^3$

Density of N₂, in $1/\text{m}^3$

Density of O₂, in $1/\text{m}^3$

Density of Ar, in $1/\text{m}^3$

Total mass density, in kg/m^3

Density of H, in $1/\text{m}^3$

Density of N, in $1/\text{m}^3$

Anomalous oxygen number density, in $1/\text{m}^3$

density(6), total mass density, is the sum of the mass densities of He, O, N₂, O₂, Ar, H, and N.

Optionally, *density(6)* can include the mass density of anomalous oxygen making *density(6)*, the effective total mass density for drag.

Examples

Calculate the temperatures, densities not including anomalous oxygen using the NRLMSISE-00 model at 10,000 m, 45 degrees latitude, -50 degrees longitude. This calculation uses the date January 4, 2007 at 0 UT. It uses default values for flux, magnetic index data, and local solar time with out-of-range actions generating warnings:

```
[T, rho] = atmosnrlmsise00( 10000, 45, -50, 2007, 4, 0)
```

```
T =
  1.0e+03 *
    1.0273    0.2212
```

```
rho =
  1.0e+24 *
    0.0000    0    6.6824    1.7927    0.0799    0.0000    0    0    0
```

Calculate the temperatures, densities not including anomalous oxygen using the NRLMSISE-00 model. Use the model at 10,000 m, 45 degrees latitude, -50 degrees longitude and 25,000 m, 47 degrees latitude, -55 degrees longitude.

This calculation uses the date January 4, 2007 at 0 UT. It uses default values for flux, magnetic index data, and local solar time with out-of-range actions generating warnings:

```
[T, rho] = atmosnrlmsise00( [10000; 25000], [45; 47], ...
[-50; -55], [2007; 2007], [4; 4], [0; 0])
```

```
T =
  1.0e+003 *
    1.0273    0.2212
    1.0273    0.2116
```

```
rho =
  1.0e+024 *
    0.0000    0    6.6824    1.7927    0.0799    0.0000    0    0    0
    0.0000    0    0.6347    0.1703    0.0076    0.0000    0    0    0
```

Calculate the temperatures, densities including anomalous oxygen using the NRLMSISE-00 model at 10,000 m, 45 degrees latitude, -50 degrees longitude. This calculation uses the date January 4, 2007 at 0 UT. It uses default values for flux, magnetic index data, and local solar time with out-of-range actions generating errors:

```
[T, rho] = atmosnrlmsise00( 10000, 45, -50, 2007, ...
4, 0, 'Oxygen', 'Error')
```

```
T =
  1.0e+003 *
    1.0273    0.2212
```

```
rho =
  1.0e+024 *
    0.0000    0    6.6824    1.7927    0.0799    0.0000    0    0    0
```

Calculate the temperatures, densities including anomalous oxygen using the NRLMSISE-00 model at 100,000 m, 45 degrees latitude, -50 degrees longitude. This calculation uses the date January 4, 2007

at 0 UT. It uses defined values for flux, and magnetic index data, and default local solar time. It specifies that the out-of-range action is to generate no message:

```
aph = [17.375 15 20 15 27 (32+22+15+22+9+18+12+15)/8 (39+27+9+32+39+9+7+12)/8]
f107 = 87.7
nov_6days = [ 78.6 78.2 82.4 85.5 85.0 84.1]
dec_31daymean = 84.5
jan_31daymean = 83.5
feb_13days = [ 89.9 90.3 87.3 83.7 83.0 81.9 82.0 78.4 76.7 75.9 74.7 73.6 72.7]
f107a = (sum(nov_6days) + sum(feb_13days) + (dec_31daymean + jan_31daymean)*31)/81
flags = ones(1,23)
flags(9) = -1
[T, rho] = atmosnr1msise00( 100000, 45, -50, 2007, 4, 0, f107a, f107, ...
aph, flags, 'Oxygen', 'None')
```

```
aph =
    17.3750    15.0000    20.0000    15.0000    27.0000    18.1250    21.7500
```

```
f107 =
```

```
    87.7000
```

```
nov_6days =
```

```
    78.6000    78.2000    82.4000    85.5000    85.0000    84.1000
```

```
dec_31daymean =
```

```
    84.5000
```

```
jan_31daymean =
```

```
    83.5000
```

```
feb_13days =
```

```
Columns 1 through 10
```

```
    89.9000    90.3000    87.3000    83.7000    83.0000    81.9000    82.0000    78.4000    76.7000    75.9000
```

```
Columns 11 through 13
```

```
    74.7000    73.6000    72.7000
```

```
f107a =
```

```
    83.3568
```

```
flags =
```

```
Columns 1 through 17
```

```
    1    1    1    1    1    1    1    1    1    1    1    1    1    1    1    1    1
```

```
Columns 18 through 23
```

```
    1    1    1    1    1    1
```

```
flags =
```

```
Columns 1 through 17
```

```
    1    1    1    1    1    1    1    1    -1    1    1    1    1    1    1    1    1
```

```
Columns 18 through 23
```

```
    1    1    1    1    1    1
```

```
T =
```

```
    1.0e+003 *
```

1.0273 0.1917

rho =

1.0e+018 *

0.0001 0.4241 7.8432 1.9721 0.0808 0.0000 0.0000 0.0000 0.0000

References

<https://ccmc.gsfc.nasa.gov/modelweb/atmos/nrlmsise00.html>

See Also

atmoscira

Introduced in R2007b

atmospalt

Calculate pressure altitude based on ambient pressure

Syntax

```
pressureAltitude = atmospalt(pressure, action)
```

Description

pressureAltitude = atmospalt(*pressure*, *action*) computes the pressure altitude based on ambient pressure. Pressure altitude is the altitude with specified ambient pressure in the 1976 Committee on Extension to the Standard Atmosphere (COESA) United States standard. Pressure altitude is the same as the mean sea level (MSL) altitude.

This function extrapolates altitude values logarithmically below the pressure of 0.3961 Pa (approximately 0.00006 psi) and above the pressure of 101,325 Pa (approximately 14.7 psi).

This function assumes that air is dry and an ideal gas.

Input Arguments

pressure

Array of *m*-by-1 ambient pressures, in pascal.

action

Action for out-of-range input. Specify one:

'Error'

'Warning' (default)

'None'

Output Arguments

pressureAltitude

Array of *m*-by-1 pressure altitudes or MSL altitudes, in meters.

Examples

Calculate the pressure altitude at a static pressure of 101,325 Pa with warnings for out-of-range inputs:

```
h = atmospalt(101325)
```

```
h =
```

```
0
```

Calculate the pressure altitude at static pressures of 101,325 Pa and 26,436 Pa with errors for out-of-range inputs:

```
h = atmospalt([101325 26436], 'Error' )
```

```
h =
```

```
1.0e+004 *
```

```
0 1.0000
```

References

U.S. Standard Atmosphere, 1976, U.S. Government Printing Office, Washington, D.C.

See Also

[atmoscira](#) | [atmoscoesa](#) | [atmosisa](#) | [atmoslapse](#) | [atmosnonstd](#)

Introduced in R2006b

Body (Aero.Body)

Construct body object for use with animation object

Syntax

```
h = Aero.Body
```

Description

`h = Aero.Body` constructs a body for an animation object. The animation object is returned in `h`. To use the `Aero.Body` object, you typically:

- 1 Create the animation body.
- 2 Configure or customize the body object.
- 3 Load the body.
- 4 Generate patches for the body (requires an axes from a figure).
- 5 Set the source for the time series data.
- 6 Move or update the body.

The animation object has the following properties:

By default, an `Aero.Body` object natively uses aerospace body coordinates for the body geometry and the time series data. Convert time series data from other coordinate systems on the fly by registering a different `CoordTransformFcn` function.

See `Aero.Body` for further details.

See Also

`Aero.Body`

Introduced in R2007a

Camera (Aero.Camera)

Construct camera object for use with animation object

Syntax

`h = Aero.Camera`

Description

`h = Aero.Camera` constructs a camera object `h` for use with an animation object. The camera object uses the registered coordinate transform. By default, this is an aerospace body coordinate system. Axes of custom coordinate systems must be orthogonal.

The animation object has the following properties:

By default, an `Aero.Body` object natively uses aerospace body coordinates for the body geometry and the time series data. Convert time series data from other coordinate systems on the fly by registering a different `CoordTransformFcn` function.

See `Aero.Camera` for further details.

See Also

`Aero.Camera`

Introduced in R2007a

camheading

Package: satelliteScenario

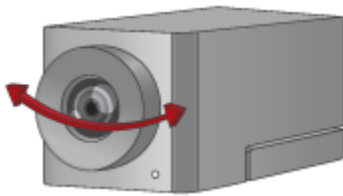
Set or get heading angle of camera for satellite scenario satellite scenario viewer

Syntax

```
camheading(viewer, heading)
outHeading = camheading(viewer, ___)
```

Description

`camheading(viewer, heading)` sets the heading angle of the camera for the specified satellite scenario viewer. Setting the heading angle shifts the camera left or right about its z - axis.



`outHeading = camheading(viewer, ___)` returns the heading angle of the camera. If the second input is heading, then the function sets the output equal to the input pitch.

Input Arguments

viewer — Satellite scenario viewer
satelliteScenarioViewer object

Satellite scenario viewer, specified as a `satelliteScenarioViewer` object. `viewer` must be specified as a scalar `satelliteScenarioViewer` object.²

heading — Heading angle of camera
360 (default) | scalar in the range [-360, 360]

Heading angle of the camera, specified as a scalar value in the range [-360, 360] degrees.

Tips

- When the pitch angle is near -90 (the default value) or 90 degrees, the camera loses one rotational degree of freedom. As a result, when you change the roll angle, the heading angle might change instead. This phenomenon is called gimbal lock. To avoid the effects of gimbal lock, call the `camheading` function instead of the `camroll` function.

2. Alignment of boundaries and region labels are a presentation of the feature provided by the data vendors and do not imply endorsement by MathWorks.

See Also

Objects

satelliteScenario | satelliteScenarioViewer

Functions

camheading | camheight | campitch | campos | camroll | camtarget | hide | hideAll | play | show

Topics

“Satellite Scenario Key Concepts” on page 2-61

Introduced in R2021a

camheight

Package: satelliteScenario

Set or get height of camera for satellite scenario viewer

Syntax

```
camheight(viewer,height)
heightOut = camheight(viewer, ___)
```

Description

`camheight(viewer,height)` sets the ellipsoidal height of the camera for the specified satellite scenario viewer.

`heightOut = camheight(viewer, ___)` returns the ellipsoidal height of the camera. If the second input is `height`, then the function sets the output equal to the input height.

Input Arguments

viewer — Satellite scenario viewer

satelliteScenarioViewer object

Satellite scenario viewer, specified as a `satelliteScenarioViewer` object. `viewer` must be specified as a scalar `satelliteScenarioViewer` object.³

height — Ellipsoidal height of camera

15000000 (default) | numeric scalar

Ellipsoidal height of the camera, specified as a numeric scalar in meters. Satellite scenario viewer objects use the WGS84 reference ellipsoid. For more information about ellipsoidal height, see “Geodetic Coordinates” on page 2-61.

If you specify the height so that the camera is level with or below the surface of the Earth, then the `camheight` function sets the height to a value one meter above the surface.

See Also

Objects

satelliteScenario | satelliteScenarioViewer

Functions

camheading | campitch | campos | camroll | camtarget | hide | hideAll | play | show

Topics

“Satellite Scenario Key Concepts” on page 2-61

3. Alignment of boundaries and region labels are a presentation of the feature provided by the data vendors and do not imply endorsement by MathWorks.

Introduced in R2021a

campitch

Package: satelliteScenario

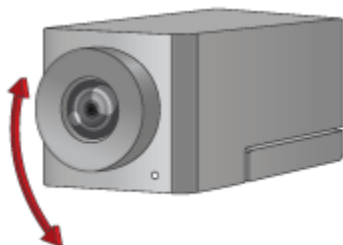
Set or get pitch angle of camera for satellite scenario viewer

Syntax

```
campitch(viewer,pitch)
outPitch = campitch(viewer, ___ )
```

Description

`campitch(viewer,pitch)` sets the pitch angle of the camera for the specified satellite scenario viewer. Setting the pitch angle tilts the camera up or down as shown in this figure..



`outPitch = campitch(viewer, ___)` returns the pitch angle of the camera. If the second input is `pitch`, then the function sets the output equal to the input pitch.

Input Arguments

viewer — Satellite scenario viewer

`satelliteScenarioViewer` object

Satellite scenario viewer, specified as a `satelliteScenarioViewer` object. `viewer` must be specified as a scalar `satelliteScenarioViewer` object.⁴

pitch — Pitch angle of camera

scalar the in the range [-90, 90]

Pitch angle of the camera, specified as a scalar the in the range [-90, 90] degrees. By default, the pitch angle is -90 degrees, which means that camera points directly toward the surface of the globe.

Tips

- When the pitch angle is near -90 (the default value) or 90 degrees, the camera loses one rotational degree of freedom. As a result, when you change the roll angle, the heading angle might change instead. This phenomenon is called gimbal lock. To avoid the effects of gimbal lock, call the `camheading` function instead of the `camroll` function.

4. Alignment of boundaries and region labels are a presentation of the feature provided by the data vendors and do not imply endorsement by MathWorks.

See Also

Objects

satelliteScenario | satelliteScenarioViewer

Functions

camheading | campitch | campos | camroll | camtarget | hide | hideAll | play | show

Topics

“Satellite Scenario Key Concepts” on page 2-61

Introduced in R2021a

campos

Package: satelliteScenario

Set or get position of camera for satellite scenario viewer

Syntax

```
campos(viewer, lat, lon)
campos(viewer, lat, lon, height)
campos(viewer)
[latOut, lonOut, heightOut] = campos( ___ )
```

Description

`campos(viewer, lat, lon)` sets the latitude and longitude of the camera for the specified satellite scenario viewer.

`campos(viewer, lat, lon, height)` sets the latitude, longitude, and ellipsoidal height of the camera. If you want to set only the height of the camera, use the `camheight` function instead.

`campos(viewer)` displays the latitude, longitude, and ellipsoidal height of the camera as a three-element vector.

`[latOut, lonOut, heightOut] = campos(___)` sets the position and then returns the latitude, longitude, and height of the camera. Specify any input argument combinations from previous syntaxes.

Input Arguments

viewer — Satellite scenario viewer

satelliteScenarioViewer object

Satellite scenario viewer, specified as a `satelliteScenarioViewer` object. `viewer` must be specified as a scalar `satelliteScenarioViewer` object.⁵

lat — Geodetic latitude of camera

0 (default) | scalar in the range [-90, 90].

Geodetic latitude of the camera, specified as a scalar in the range [-90, 90] degrees.

lon — Geodetic longitude of camera

0 (default) | scalar in the range [-360, 360].

Geodetic longitude of the camera, specified as a scalar in the range [-360, 360].

height — Ellipsoidal height of camera

15000000 (default) | numeric scalar

5. Alignment of boundaries and region labels are a presentation of the feature provided by the data vendors and do not imply endorsement by MathWorks.

Ellipsoidal height of the camera, specified as a numeric scalar in meters. Satellite scenario viewer objects use the WGS84 reference ellipsoid.

If you specify the height so that the camera is level with or below the surface of the Earth, then the `campos` function sets the height to a value one meter above the surface.

Output Arguments

latOut — Geodetic latitude of camera

numeric scalar

Geodetic latitude of the camera, returned as a numeric scalar in degrees.

lonOut — Geodetic longitude of camera

numeric scalar

Geodetic longitude of the camera, returned as a numeric scalar in degrees.

heightOut — Ellipsoidal height of camera

numeric scalar

Ellipsoidal height of the camera, returned as a numeric scalar in meters. Satellite scenario viewer objects use the WGS84 reference ellipsoid. For more information about ellipsoidal height, see “Geodetic Coordinates” on page 2-61.

See Also

Objects

`satelliteScenario` | `satelliteScenarioViewer`

Functions

`camheading` | `camheight` | `campitch` | `camroll` | `camtarget` | `hide` | `hideAll` | `play` | `show`

Topics

“Satellite Scenario Key Concepts” on page 2-61

Introduced in R2021a

camroll

Package: satelliteScenario

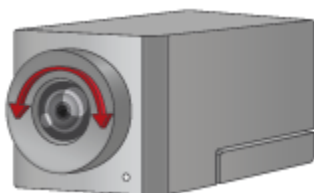
Set or get roll angle of camera for satellite scenario viewer

Syntax

```
camroll(viewer,roll)
outRoll = camroll(viewer, ___)
```

Description

`camroll(viewer,roll)` sets the roll angle of the camera for the satellite scenario viewer. Setting the roll angle rotates the camera around its x-axis.



`outRoll = camroll(viewer, ___)` returns the roll angle of the camera. If the second input is `roll`, then the function sets the output equal to the input `roll`.

Input Arguments

viewer — Satellite scenario viewer
satelliteScenarioViewer object

Satellite scenario viewer, specified as a `satelliteScenarioViewer` object. `viewer` must be specified as a scalar `satelliteScenarioViewer` object.⁶

roll — Roll angle of camera
scalar in the range [-360, 360]

Roll angle of the camera, specified as a scalar in the range [-360, 360] degrees.

Tips

- When the pitch angle is near -90 (the default value) or 90 degrees, the camera loses one rotational degree of freedom. As a result, when you change the roll angle, the heading angle might change instead. This phenomenon is called gimbal lock. To avoid the effects of gimbal lock, call the `camheading` function instead of the `camroll` function.

6. Alignment of boundaries and region labels are a presentation of the feature provided by the data vendors and do not imply endorsement by MathWorks.

See Also

Objects

satelliteScenario | satelliteScenarioViewer

Functions

camheading | camheight | campitch | campos | camtarget | hide | hideAll | play | show

Topics

“Satellite Scenario Key Concepts” on page 2-61

Introduced in R2021a

camtarget

Package: satelliteScenario

Set camera target for satellite scenario viewer

Syntax

```
camtarget(viewer, target)
```

Description

`camtarget(viewer, target)` focuses the camera on the input satellite or ground station. The camera follows the object and can be unlocked by calling `camtarget` on another satellite or ground station or by double-clicking anywhere in the map.

Input Arguments

viewer — Satellite scenario viewer

`satelliteScenarioViewer` object

Satellite scenario viewer, specified as a `satelliteScenarioViewer` object. `viewer` must be specified as a scalar `satelliteScenarioViewer` object.⁷

target — Target of camera

`Satellite` object | `GroundStation` object

Target of the camera, specified as a scalar `Satellite` or `GroundStation` object.

See Also

Objects

`satelliteScenario` | `satelliteScenarioViewer`

Functions

`camheading` | `camheight` | `campitch` | `campos` | `camroll` | `hide` | `hideAll` | `play` | `show`

Topics

“Satellite Scenario Key Concepts” on page 2-61

Introduced in R2021a

7. Alignment of boundaries and region labels are a presentation of the feature provided by the data vendors and do not imply endorsement by MathWorks.

ClearTimer (Aero.FlightGearAnimation)

Clear and delete timer for animation of FlightGear flight simulator

Syntax

```
ClearTimer(h)  
h.ClearTimer
```

Description

ClearTimer(h) and h.ClearTimer clear and delete the MATLAB timer for the animation of the FlightGear flight simulator.

Examples

Clear and delete the MATLAB timer for animation of the FlightGear animation object, h:

```
h = Aero.FlightGearAnimation  
h.SetTimer  
h.ClearTimer  
h.SetTimer('FGTimer')
```

See Also

SetTimer

Introduced in R2008b

ClimbIndicator Properties

Control climb indicator appearance and behavior

Description

Climb indicators are components that represent a climb indicator. Properties control the appearance and behavior of a climb indicator. Use dot notation to refer to a particular object and property.

```
f = uifigure;
climbindicator = uiaeroclimb(f);
climbindicator.ClimbRate = 100;
```

The climb rate indicator displays measurements for an aircraft climb rate in ft/min.

The needle covers the top semicircle, if the velocity is positive, and the lower semicircle, if the climb rate is negative. The range of the indicator is from **-Maximum** feet per minute to **Maximum** feet per minute. Major ticks indicate **Maximum/4**. Minor ticks indicate **Maximum/8** and **Maximum/80**.

Properties

Climb Indicator

ClimbRate — Climb rate of aircraft

0 (default) | finite, real, and scalar numeric

Climb rate of the aircraft, specified as a finite, real, and scalar numeric, in ft/min.

Example: 60

Dependencies

Specifying this value changes the value of `Value`.

Data Types: `double`

MaximumRate — Maximum gauge scale values

0 (default) | finite, real, positive, and scalar numeric

Maximum gauge scale values, specified as a finite, real, positive, and scalar numeric, representing the +/- maximum climb rate, in ft/min.

Example: 100

Data Types: `double`

Value — Climb rate of aircraft

0 (default) | finite, real, and scalar numeric

Climb rate of the aircraft, specified as a finite, real, and scalar numeric, in ft/min.

Example: 60

Dependencies

Specifying this value changes the value of `ClimbRate`.

Data Types: `double`

Interactivity**Visible — Visibility of climb indicator**

'on' (default) | on/off logical value

Visibility of the climb indicator, specified as 'on' or 'off', or as numeric or logical 1 (true) or 0 (false). A value of 'on' is equivalent to true, and 'off' is equivalent to false. Thus, you can use the value of this property as a logical value. The value is stored as an on/off logical value of type `matlab.lang.OnOffSwitchState`. The `Visible` property determines whether the climb indicator is displayed on the screen. If the `Visible` property is set to 'off', then the entire climb indicator is hidden, but you can still specify and access its properties.

ContextMenu — Context menu

empty `GraphicsPlaceholder` array (default) | `ContextMenu` object

Context menu, specified as a `ContextMenu` object created using the `uicontextmenu` function. Use this property to display a context menu when you right-click on a component.

Enable — Operational state of climb indicator

'on' (default) | on/off logical value

Operational state of climb indicator, specified as 'on' or 'off', or as numeric or logical 1 (true) or 0 (false). A value of 'on' is equivalent to true, and 'off' is equivalent to false. Thus, you can use the value of this property as a logical value. The value is stored as an on/off logical value of type `matlab.lang.OnOffSwitchState`.

- If you set this property to 'on', then the appearance of the climb indicator indicates that the climb indicator is operational.
- If you set this property to 'off', then the appearance of the climb indicator appears dimmed, indicating that the climb indicator is not operational.

Position**Position — Location and size of climb indicator**

[100 100 120 120] (default) | [left bottom width height]

Location and size of the climb indicator relative to the parent container, specified as the vector, [left bottom width height]. This table describes each element in the vector.

Element	Description
left	Distance from the inner left edge of the parent container to the outer left edge of an imaginary box surrounding the climb indicator
bottom	Distance from the inner bottom edge of the parent container to the outer bottom edge of an imaginary box surrounding the climb indicator

Element	Description
width	Distance between the right and left outer edges of the climb indicator
height	Distance between the top and bottom outer edges of the climb indicator

All measurements are in pixel units.

The `Position` values are relative to the drawable area of the parent container. The drawable area is the area inside the borders of the container and does not include the area occupied by decorations such as a menu bar or title.

Example: `[200 120 120 120]`

InnerPosition — Inner location and size of climb indicator

`[100 100 120 120]` (default) | `[left bottom width height]`

Inner location and size of the climb indicator, specified as `[left bottom width height]`. Position values are relative to the parent container. All measurements are in pixel units. This property value is identical to the `Position` property.

OuterPosition — Outer location and size of climb indicator

`[100 100 120 120]` (default) | `[left bottom width height]`

This property is read-only.

Outer location and size of the climb indicator returned as `[left bottom width height]`. Position values are relative to the parent container. All measurements are in pixel units. This property value is identical to the `Position` property.

Layout — Layout options

empty `LayoutOptions` array (default) | `GridLayoutOptions` object

Layout options, specified as a `GridLayoutOptions` object. This property specifies options for components that are children of grid layout containers. If the component is not a child of a grid layout container (for example, it is a child of a figure or panel), then this property is empty and has no effect. However, if the component is a child of a grid layout container, you can place the component in the desired row and column of the grid by setting the `Row` and `Column` properties on the `GridLayoutOptions` object.

For example, this code places an climb rate indicator in the third row and second column of its parent grid.

```
g = ui([4 3]);
gauge = uiaeroclimb(g);
gauge.Layout.Row = 3;
gauge.Layout.Column = 2;
```

To make the climb rate indicator span multiple rows or columns, specify the `Row` or `Column` property as a two-element vector. For example, this climb rate indicator spans columns 2 through 3:

```
gauge.Layout.Column = [2 3];
```

Callbacks

CreateFcn — Creation function

' ' (default) | function handle | cell array | character vector

Object creation function, specified as one of these values:

- Function handle.
- Cell array in which the first element is a function handle. Subsequent elements in the cell array are the arguments to pass to the callback function.
- Character vector containing a valid MATLAB expression (not recommended). MATLAB evaluates this expression in the base workspace.

For more information about specifying a callback as a function handle, cell array, or character vector, see “Write Callbacks in App Designer”.

This property specifies a callback function to execute when MATLAB creates the object. MATLAB initializes all property values before executing the `CreateFcn` callback. If you do not specify the `CreateFcn` property, then MATLAB executes a default creation function.

Setting the `CreateFcn` property on an existing component has no effect.

If you specify this property as a function handle or cell array, you can access the object that is being created using the first argument of the callback function. Otherwise, use the `gcbo` function to access the object.

DeleteFcn — Deletion function

' ' (default) | function handle | cell array | character vector

Object deletion function, specified as one of these values:

- Function handle.
- Cell array in which the first element is a function handle. Subsequent elements in the cell array are the arguments to pass to the callback function.
- Character vector containing a valid MATLAB expression (not recommended). MATLAB evaluates this expression in the base workspace.

For more information about specifying a callback as a function handle, cell array, or character vector, see “Write Callbacks in App Designer”.

This property specifies a callback function to execute when MATLAB deletes the object. MATLAB executes the `DeleteFcn` callback before destroying the properties of the object. If you do not specify the `DeleteFcn` property, then MATLAB executes a default deletion function.

If you specify this property as a function handle or cell array, you can access the object that is being deleted using the first argument of the callback function. Otherwise, use the `gcbo` function to access the object.

Callback Execution Control

Interruptible — Callback interruption

' on ' (default) | on/off logical value

Callback interruption, specified as 'on' or 'off', or as numeric or logical 1 (true) or 0 (false). A value of 'on' is equivalent to true, and 'off' is equivalent to false. Thus, you can use the value

of this property as a logical value. The value is stored as an on/off logical value of type `matlab.lang.OnOffSwitchState`.

This property determines if a running callback can be interrupted. There are two callback states to consider:

- The running callback is the currently executing callback.
- The interrupting callback is a callback that tries to interrupt the running callback.

Whenever MATLAB invokes a callback, that callback attempts to interrupt the running callback (if one exists). The `Interruptible` property of the object owning the running callback determines if interruption is allowed.

- A value of 'on' allows other callbacks to interrupt the object's callbacks. The interruption occurs at the next point where MATLAB processes the queue, such as when there is a `drawnow`, `figure`, `uifigure`, `getframe`, `waitfor`, or `pause` command.
 - If the running callback contains one of those commands, then MATLAB stops the execution of the callback at that point and executes the interrupting callback. MATLAB resumes executing the running callback when the interrupting callback completes.
 - If the running callback does not contain one of those commands, then MATLAB finishes executing the callback without interruption.
- A value of 'off' blocks all interruption attempts. The `BusyAction` property of the object owning the interrupting callback determines if the interrupting callback is discarded or put into a queue.

Note Callback interruption and execution behave differently in these situations:

- If the interrupting callback is a `DeleteFcn`, `CloseRequestFcn` or `SizeChangedFcn` callback, then the interruption occurs regardless of the `Interruptible` property value.
- If the running callback is currently executing the `waitfor` function, then the interruption occurs regardless of the `Interruptible` property value.
- Timer objects execute according to schedule regardless of the `Interruptible` property value.

When an interruption occurs, MATLAB does not save the state of properties or the display. For example, the object returned by the `gca` or `gcf` command might change when another callback executes.

BusyAction — Callback queuing

'queue' (default) | 'cancel'

Callback queuing, specified as 'queue' or 'cancel'. The `BusyAction` property determines how MATLAB handles the execution of interrupting callbacks. There are two callback states to consider:

- The running callback is the currently executing callback.
- The interrupting callback is a callback that tries to interrupt the running callback.

Whenever MATLAB invokes a callback, that callback attempts to interrupt a running callback. The `Interruptible` property of the object owning the running callback determines if interruption is permitted. If interruption is not permitted, then the `BusyAction` property of the object owning the interrupting callback determines if it is discarded or put in the queue. These are possible values of the `BusyAction` property:

- 'queue' — Puts the interrupting callback in a queue to be processed after the running callback finishes execution.
- 'cancel' — Does not execute the interrupting callback.

BeingDeleted — Deletion status

on/off logical value

This property is read-only.

Deletion status, returned as an on/off logical value of type `matlab.lang.OnOffSwitchState`.

MATLAB sets the `BeingDeleted` property to 'on' when the `DeleteFcn` callback begins execution. The `BeingDeleted` property remains set to 'on' until the component object no longer exists.

Check the value of the `BeingDeleted` property to verify that the object is not about to be deleted before querying or modifying it.

Parent/Child

HandleVisibility — Visibility of object handle

'on' (default) | 'callback' | 'off'

Visibility of the object handle, specified as 'on', 'callback', or 'off'.

This property controls the visibility of the object in its parent's list of children. When an object is not visible in its parent's list of children, it is not returned by functions that obtain objects by searching the object hierarchy or querying properties. These functions include `get`, `findobj`, `clf`, and `close`. Objects are valid even if they are not visible. If you can access an object, you can set and get its properties, and pass it to any function that operates on objects.

HandleVisibility Value	Description
'on'	The object is always visible.
'callback'	The object is visible from within callbacks or functions invoked by callbacks, but not from within functions invoked from the command line. This option blocks access to the object at the command-line, but allows callback functions to access it.
'off'	The object is invisible at all times. This option is useful for preventing unintended changes to the UI by another function. Set the <code>HandleVisibility</code> to 'off' to temporarily hide the object during the execution of that function.

Parent — Parent container

Figure object (default) | Panel object | Tab object | ButtonGroup object | GridLayout object

Parent container, specified as a Figure object created using the `uifigure` function, or one of its child containers: `Tab`, `Panel`, `ButtonGroup`, or `GridLayout`. If no container is specified, MATLAB calls the `uifigure` function to create a new Figure object that serves as the parent container.

Identifiers

Type — Type of graphics object

'uiaeroclimb'

This property is read-only.

Type of graphics object, returned as `'uiaerohorizon'`.

Tag – Object identifier

`''` (default) | character vector | string scalar

Object identifier, specified as a character vector or string scalar. You can specify a unique `Tag` value to serve as an identifier for an object. When you need access to the object elsewhere in your code, you can use the `findobj` function to search for the object based on the `Tag` value.

UserData – User data

`[]` (default) | array

User data, specified as any MATLAB array. For example, you can specify a scalar, vector, matrix, cell array, character array, table, or structure. Use this property to store arbitrary data on an object.

If you are working in App Designer, create public or private properties in the app to share data instead of using the `UserData` property. For more information, see “Share Data Within App Designer Apps”.

See Also

`uiaeroclimb`

Topics

“Create and Configure Flight Instrument Component and an Animation Object” on page 2-49

“Display Flight Trajectory Data Using Flight Instruments and Flight Animation” on page 5-111

Introduced in R2018b

conicalSensor

Package: satelliteScenario

Add conical sensor to satellite scenario

Syntax

```
conicalSensor(parent)
conicalSensor(parent,Name,Value)
S = conicalSensor( ___ )
```

Description

`conicalSensor(parent)` adds a default `ConicalSensor` object to `parent` which can be a `satellite`, `groundStation` or `gimbal`.

`conicalSensor(parent,Name,Value)` specifies options using one or more name-value arguments. For example, `'MaxViewAngle',90` specifies a field of view angle of 90 degrees.

`S = conicalSensor(___)` returns a handle to the added conical sensor. Specify any input argument combination from previous syntaxes.

Input Arguments

parent — Element of scenario to which conicalSensor is added

Satellite object | GroundStation object | Gimbal object

Element of scenario to which the `conicalSensor` is added, specified as a `Satellite`, `GroundStation`, or `Gimbal` object.

Name-Value Pair Arguments

Specify optional comma-separated pairs of `Name,Value` arguments. `Name` is the argument name and `Value` is the corresponding value. `Name` must appear inside quotes. You can specify several name and value pair arguments in any order as `Name1,Value1,...,NameN,ValueN`.

Example: `'MountingAngle',[20; 35; 10]` sets the yaw, pitch, and roll angles of the conical sensor to 20, 35, and 10 degrees, respectively.

Name — conicalSensor name

"conicalSensor *idx*" (default) | string scalar | string vector | character vector | cell array of character vectors

You can set this property only when calling `conicalSensor`. After you call `conicalSensor`, this property is read-only.

`conicalSensor` name, specified as a comma-separated pair consisting of `'Name'` and a string scalar, string vector, character vector or a cell array of character vectors.

- If only one `conicalSensor` is added, specify `Name` as a string scalar or a character vector.

- If multiple conicalSensors are added, specify Name as a string vector or a cell array of character vectors. The number of elements in the string vector or cell array must be equal to the number of satellites being added.

In the default value, *idx* is the count of the conicalSensor added by the conicalSensor object function. If another conicalSensor of the same name exists, a suffix *_idx₂* is added, where *idx₂* is an integer that is incremented by 1 starting from 1 until the name duplication is resolved.

Data Types: char | string

MountingLocation — Mounting location with respect to parent

[0; 0; 0] (default) | three-element row vector of positive numbers

Mounting location with respect to the parent object, specified as a three-element row vector of positive numbers in meters. The position vector is specified in the body frame of the input parent.

MountingAngles — Mounting orientation with respect to parent object

[0; 0; 0] (default) | three-element row vector of positive numbers

Mounting orientation with respect to parent object, specified as a three-element row vector of positive numbers in degrees. The elements of the vector correspond to yaw, pitch, and roll in that order. Yaw, pitch, and roll are positive rotations about the parent's *z* - axis, intermediate *y* - axis and intermediate *x* - axis of the parent.

Example: [0; 30; 60]

MaxViewAngle — Field of view angle

30 (default) | scalar in the range [0, 180]

Field of view angle, specified as a scalar in the range [0, 180]. Units are in degrees.

Output Arguments

S — Conical sensor

ConicalSensor object

Conical sensor attached to parent, returned as a ConicalSensor object.

See Also

Objects

satelliteScenario | satelliteScenarioViewer

Functions

access | gimbal | groundStation | hide | play | satellite | show

Topics

"Satellite Scenario Key Concepts" on page 2-61

Introduced in R2021a

ConicalSensor

Conical sensor object belonging to satellite scenario

Description

ConicalSensor defines a conical sensor object belonging to a satellite scenario.

Creation

You can create the ConicalSensor object using the conicalSensor object function of the Satellite or GroundStation objects.

Properties

Name — ConicalSensor name

"ConicalSensor *idx*" (default) | string scalar | string vector | character vector | cell array of character vectors

You can set this property only when calling ConicalSensor. After you call ConicalSensor, this property is read-only.

ConicalSensor name, specified as a comma-separated pair consisting of 'Name' and a string scalar, string vector, character vector or a cell array of character vectors.

- If only one ConicalSensor is added, specify Name as a string scalar or a character vector.
- If multiple ConicalSensors are added, specify Name as a string vector or a cell array of character vectors. The number of elements in the string vector or cell array must be equal to the number of satellites being added.

In the default value, *idx* is the count of the ConicalSensor added by the ConicalSensor object function. If another ConicalSensor of the same name exists, a suffix *_idx₂* is added, where *idx₂* is an integer that is incremented by 1 starting from 1 until the name duplication is resolved.

Data Types: char | string

ID — ConicalSensor ID assigned by simulator

real positive scalar

This property is set internally by the simulator and is read-only.

ConicalSensor ID assigned by the simulator, specified as a positive scalar.

MountingLocation — Mounting location with respect to parent

[0; 0; 0] (default) | three-element row vector of positive numbers

Mounting location with respect to the parent object, specified as a three-element row vector of positive numbers in meters. The position vector is specified in the body frame of the input parent.

MaxViewAngle — Field of view angle

30 (default) | scalar in the range [0, 180]

Field of view angle, specified as a scalar in the range [0, 180]. Units are in degrees.

Accesses — Access analysis objects

row vector of Access objects

You can set this property only when calling ConicalSensor. After you call ConicalSensor, this property is read-only.

Access analysis objects, specified as a row vector of Access objects.

FieldOfView — Field of view objects

row vector of FieldOfView objects

You can set this property only when calling ConicalSensor. After you call ConicalSensor, this property is read-only.

Field of view objects, specified as a scalar of FieldOfView objects.

Object Functions

access Add access analysis objects to satellite scenario
fieldOfView Visualize field of view of conical sensor

See Also**Objects**

satelliteScenario | satelliteScenarioViewer

Functions

access | groundStation | hide | play | show

Topics

"Satellite Scenario Key Concepts" on page 2-61

Introduced in R2021a

convacc

Convert from acceleration units to desired acceleration units

Syntax

```
convertedValues = convacc(valuesToConvert, inputAccelUnits, outputAccelUnits)
```

Description

convertedValues = convacc(*valuesToConvert*, *inputAccelUnits*, *outputAccelUnits*) computes the conversion factor from specified input acceleration units to specified output acceleration units. It then applies the conversion factor to the input to produce the output in the desired units.

Input Arguments

valuesToConvert

Floating-point array of size *m-by-n* values that the function is to convert. All values must have the same unit conversions from *inputAccelUnits* to *outputAccelUnits*.

inputAccelUnits

Specified input acceleration units. Supported units are:

'ft/s^2'	Feet per second squared
'm/s^2'	Meters per second squared
'km/s^2'	Kilometers per second squared
'in/s^2'	Inches per second squared
'km/h-s'	Kilometers per hour per second
'mph/s'	Miles per hour per second
'G's'	G-force (G's) acceleration

outputAccelUnits

Specified output acceleration units. Supported units are:

'ft/s^2'	Feet per second squared
'm/s^2'	Meters per second squared
'km/s^2'	Kilometers per second squared
'in/s^2'	Inches per second squared
'km/h-s'	Kilometers per hour per second
'mph/s'	Miles per hour per second
'G's'	g-units

Output Arguments

convertedValues

Floating-point array of size m -by- n values that the function has converted.

Examples

Convert three accelerations from feet per second squared to meters per second squared:

```
a = convacc([3 10 20], 'ft/s^2', 'm/s^2')
```

```
a =
```

```
    0.9144    3.0480    6.0960
```

See Also

[convang](#) | [convangacc](#) | [convangvel](#) | [convdensity](#) | [convforce](#) | [convlength](#) | [convmass](#) | [convpres](#) | [convtemp](#) | [convvel](#)

Introduced in R2006b

convang

Convert from angle units to desired angle units

Syntax

```
convertedValues = convang(valuesToConvert, inputAngleUnits, outputAngleUnits)
```

Description

convertedValues = convang(*valuesToConvert*, *inputAngleUnits*, *outputAngleUnits*) computes the conversion factor from specified input angle units to specified output angle units. It then applies the conversion factor to the input to produce the output in the desired units. *inputAngleUnits* and *outputAngleUnits* are character vectors or strings.

Input Arguments

valuesToConvert

Floating-point array of size *m*-by-*n* values the function is to convert. All values must have the same unit conversions from *inputAngleUnits* to *outputAngleUnits*.

inputAngleUnits

Specified input angle units. Supported units are:

'deg'	Degrees
'rad'	Radians
'rev'	Revolutions

outputAngleUnits

Specified output angle units. Supported units are:

'deg'	Degrees
'rad'	Radians
'rev'	Revolutions

Output Arguments

convertedValues

Floating-point array of size *m*-by-*n* values that the function has converted.

Examples

Convert three angles from degrees to radians:

```
a = convang([3 10 20], 'deg', 'rad')
```

```
a =
```

```
    0.0524    0.1745    0.3491
```

See Also

convacc | convangacc | convangvel | convdensity | convforce | convlength | convmass | convpres | convtemp | convvel

Introduced in R2006b

convangacc

Convert from angular acceleration units to desired angular acceleration units

Syntax

```
convertedValues = convangacc(valuesToConvert, inputAngularUnits,  
outputAngularUnits)
```

Description

convertedValues = convangacc(*valuesToConvert*, *inputAngularUnits*, *outputAngularUnits*) computes the conversion factor from specified input angular acceleration units to specified output angular acceleration units. It then applies the conversion factor to the input to produce the output in the desired units.

Input Arguments

valuesToConvert

Floating-point array of size *m*-by-*n* values that the function is to convert. All values must have the same unit conversions from *inputAngularUnits* to *outputAngularUnits*.

inputAngularUnits

Specified input angular acceleration units. Supported units are:

'deg/s^2'	Degrees per second squared
'rad/s^2'	Radians per second squared
'rpm/s'	Revolutions per minute per second

outputAngularUnits

Specified output angular acceleration units. Supported units are:

'deg/s^2'	Degrees per second squared
'rad/s^2'	Radians per second squared
'rpm/s'	Revolutions per minute per second

Output Arguments

convertedValues

Floating-point array of size *m*-by-*n* values that the function has converted.

Examples

Convert three angular accelerations from degrees per second squared to radians per second squared:


```
a = convangacc([0.3 0.1 0.5], 'deg/s^2', 'rad/s^2')
```

```
a =
```

```
    0.0052    0.0017    0.0087
```

See Also

[convacc](#) | [convang](#) | [convangvel](#) | [convdensity](#) | [convforce](#) | [convlength](#) | [convmass](#) | [convpres](#) | [convtemp](#) | [convvel](#)

Introduced in R2006b

convangvel

Convert from angular velocity units to desired angular velocity units

Syntax

```
convertedValues = convangvel(valuesToConvert, inputAngularVelocityUnits,  
outputAngularVelocityUnits)
```

Description

convertedValues = convangvel(*valuesToConvert*, *inputAngularVelocityUnits*, *outputAngularVelocityUnits*) computes the conversion factor from specified input angular velocity units to specified output angular velocity units. It then applies the conversion factor to the input to produce the output in the desired units.

Input Arguments

valuesToConvert

Floating-point array of size *m-by-n* values that the function is to convert. All values must have the same unit conversions from *inputAngularVelocityUnits* to *outputAngularVelocityUnits*.

inputAngularVelocityUnits

Specified input angular velocity units. Supported units are:

'deg/s'	Degrees per second
'rad/s'	Radians per second
'rpm'	Revolutions per minute

outputAngularVelocityUnits

Specified output angular velocity units. Supported units are:

'deg/s'	Degrees per second
'rad/s'	Radians per second
'rpm'	Revolutions per minute

Output Arguments

convertedValues

Floating-point array of size *m-by-n* values that the function has converted.

Examples

Convert three angular velocities from degrees per second to radians per second:

```
a = convangvel([0.3 0.1 0.5], 'deg/s', 'rad/s')
```

```
a =
```

```
    0.0052    0.0017    0.0087
```

See Also

convacc | convang | convangacc | convdensity | convforce | convlength | convmass | convpres | convtemp | convvel

Introduced in R2006b

convdensity

Convert from density units to desired density units

Syntax

```
convertedValues = convdensity(valuesToConvert, inputDensityUnits,  
outputDensityUnits)
```

Description

convertedValues = convdensity(*valuesToConvert*, *inputDensityUnits*, *outputDensityUnits*) computes the conversion factor from specified input density units to specified output density units. It then applies the conversion factor to the input to produce the output in the desired units.

Input Arguments

valuesToConvert

Floating-point array of size *m*-by-*n* values that the function is to convert. All values must have the same unit conversions from *inputDensityUnits* to *outputDensityUnits*.

inputDensityUnits

Specified input density units. Supported units are:

'lbm/ft^3'	Pound mass per feet cubed
'kg/m^3'	Kilograms per meters cubed
'slug/ft^3'	Slugs per feet cubed
'lbm/in^3'	Pound mass per inch cubed

outputDensityUnits

Specified output density units. Supported units are:

'lbm/ft^3'	Pound mass per feet cubed
'kg/m^3'	Kilograms per meters cubed
'slug/ft^3'	Slugs per feet cubed
'lbm/in^3'	Pound mass per inch cubed

Output Arguments

convertedValues

Floating-point array of size *m*-by-*n* values that the function has converted.

Examples

Convert three densities from pound mass per feet cubed to kilograms per meters cubed:

```
a = convdensity([0.3 0.1 0.5], 'lbm/ft^3', 'kg/m^3')
```

```
a =
```

```
    4.8055    1.6018    8.0092
```

See Also

[convacc](#) | [convang](#) | [convangacc](#) | [convangvel](#) | [convforce](#) | [convlength](#) | [convmass](#) | [convpres](#) | [convtemp](#) | [convvel](#)

Introduced in R2006b

convforce

Convert from force units to desired force units

Syntax

```
convertedValues = convforce(valuesToConvert, inputForceUnits,  
outputForceUnits)
```

Description

convertedValues = convforce(*valuesToConvert*, *inputForceUnits*, *outputForceUnits*) computes the conversion factor from specified input force units to specified output force units. It then applies the conversion factor to the input to produce the output in the desired units.

Input Arguments

valuesToConvert

Floating-point array of size *m*-by-*n* values that the function is to convert. All values must have the same unit conversions from *inputForceUnits* to *outputForceUnits*.

inputForceUnits

Specified input force units. Supported units are:

'lbf'	Pound force
'N'	Newton

outputForceUnits

Specified output force units. Supported units are:

'lbf'	Pound force
'N'	Newton

Output Arguments

convertedValues

Floating-point array of size *m*-by-*n* values that the function has converted.

Examples

Convert three forces from pound force to newtons:

```
a = convforce([120 1 5], 'lbf', 'N')
```

a =

533.7866 4.4482 22.2411

See Also

convacc | convang | convangacc | convangvel | convdensity | convlength | convmass | convpres | convtemp | convvel

Introduced in R2006b

convlength

Convert from length units to desired length units

Syntax

```
convertedValues = convlength(valuesToConvert, inputLengthUnits,  
outputLengthUnits)
```

Description

`convertedValues = convlength(valuesToConvert, inputLengthUnits, outputLengthUnits)` converts `valuesToConvert` from original units to desired units using computed conversion factor.

Examples

Convert Lengths

Convert three lengths from feet to meters.

```
a = convlength([3 10 20], 'ft', 'm')
```

```
a = 1×3
```

```
    0.9144    3.0480    6.0960
```

Input Arguments

valuesToConvert — Input lengths to convert

floating-point array of m -by- n values

Input lengths to convert, specified as a floating-point array of m -by- n values, in original units. All values must have the same units.

Data Types: double

inputLengthUnits — Original unit

'ft' | 'm' | 'km' | 'in' | 'naut mi'

Original unit of input lengths, specified as:

'ft'	Feet
'm'	Meters
'km'	Kilometers
'in'	Inches

'mi'	Miles
'naut mi'	Nautical miles

Data Types: char | string

outputLengthUnits — Units to convert to

'ft' | 'm' | 'km' | 'in' | 'naut mi'

New unit to convert to, specified as:

'ft'	Feet
'm'	Meters
'km'	Kilometers
'in'	Inches
'mi'	Miles
'naut mi'	Nautical miles

Data Types: char | string

Output Arguments

convertedValues — Converted lengths

floating-point array of size *m*-by-*n* values

Converted lengths, returned in new units.

See Also

convacc | convang | convangacc | convangvel | convdensity | convforce | convmass | convpres | convtemp | convvel

Introduced in R2006b

convmass

Convert from mass units to desired mass units

Syntax

```
convertedValues = convmass(valuesToConvert, inputMassUnits, outputMassUnits)
```

Description

convertedValues = convmass(*valuesToConvert*, *inputMassUnits*, *outputMassUnits*) computes the conversion factor from specified input mass units to specified output mass units. It then applies the conversion factor to the input to produce the output in the desired units.

Input Arguments

valuesToConvert

Floating-point array of size *m*-by-*n* values that the function is to convert. All values must have the same unit conversions from *inputMassUnits* to *outputMassUnits*.

inputMassUnits

Specified input mass units. Supported units are:

'lbm'	Pound mass
'kg'	Kilograms
'slug'	Slugs

outputMassUnits

Specified output mass units. Supported units are:

'lbm'	Pound mass
'kg'	Kilograms
'slug'	Slugs

Output Arguments

convertedValues

Floating-point array of size *m*-by-*n* values that the function has converted.

Examples

Convert three masses from pound mass to kilograms:

```
a = convmass([3 1 5], 'lbm', 'kg')
```

a =

1.3608 0.4536 2.2680

See Also

convacc | convang | convangacc | convangvel | convdensity | convforce | convlength | convpres | convtemp | convvel

Introduced in R2006b

convpres

Convert from pressure units to desired pressure units

Syntax

```
convertedValues = convpres(valuesToConvert, inputPressureUnits,  
outputPressureUnits)
```

Description

convertedValues = convpres(*valuesToConvert*, *inputPressureUnits*, *outputPressureUnits*) computes the conversion factor from specified input pressure units to specified output pressure units. It then applies the conversion factor to the input to produce the output in the desired units.

Input Arguments

valuesToConvert

Floating-point array of size *m*-by-*n* values that the function is to convert. All values must have the same unit conversions from *inputPressureUnits* to *outputPressureUnits*.

inputPressureUnits

Specified input pressure units. Supported units are:

'psi'	Pound force per square inch
'Pa'	Pascal
'psf'	Pound force per square foot
'atm'	Atmosphere

outputPressureUnits

Specified output pressure units. Supported units are:

'psi'	Pound force per square inch
'Pa'	Pascal
'psf'	Pound force per square foot
'atm'	Atmosphere

Output Arguments

convertedValues

Floating-point array of size *m*-by-*n* values that the function has converted.

Examples

Convert two pressures from pound force per square inch to atmospheres:

```
a = convpres([14.696 35], 'psi', 'atm')
```

```
a =
```

```
    1.0000    2.3816
```

See Also

[convacc](#) | [convang](#) | [convangacc](#) | [convangvel](#) | [convdensity](#) | [convforce](#) | [convlength](#) | [convmass](#) | [convtemp](#) | [convvel](#)

Introduced in R2006b

convtemp

Convert to desired temperature units

Syntax

```
convertedValues = convtemp(valuesToConvert,inputTemperatureUnits,  
outputTemperatureUnits)
```

Description

`convertedValues = convtemp(valuesToConvert,inputTemperatureUnits,outputTemperatureUnits)` computes the conversion factor from specified input temperature units (`inputTemperatureUnits`) to specified output temperature units (`outputTemperatureUnits`). The function then applies the conversion factor to the `valuesToConvert`.

Examples

Convert Temperatures

Convert temperatures

Convert three temperatures from degrees Celsius to degrees Fahrenheit.

```
a = convtemp([0 100 15], 'C', 'F')
```

```
a = 1×3
```

```
    32.0000    212.0000    59.0000
```

Input Arguments

valuesToConvert — Temperatures to convert

m-by-*n* floating-point array

Temperatures to convert, specified as an *m*-by-*n* floating-point array. All values must have the same units to be converted.

Data Types: `double` | `single`

inputTemperatureUnits — Unit of temperature to convert

'K' | 'F' | 'C' | 'R'

Unit of temperature to convert:

'K'	Kelvin
'F'	Degree Fahrenheit
'C'	Degree Celsius

'R' Degree Rankine

Data Types: char | string

outputTemperatureUnits — Unit of temperature to convert to

'K' | 'F' | 'C' | 'R'

Unit of temperature to convert to:

'K' Kelvin
'F' Degree Fahrenheit
'C' Degree Celsius
'R' Degree Rankine

Data Types: char | string

Output Arguments

convertedValues — Converted temperature

m-by-*n* floating-point array

Converted temperature, output as a floating-point array.

See Also

convacc | convang | convangacc | convangvel | convdensity | convforce | convlength | convmass | convpres | convvel

Topics

“Floating-Point Numbers”

Introduced in R2006b

convvel

Convert from velocity units to desired velocity units

Syntax

```
convertedValues = convvel(valuesToConvert, inputVelocityUnits,  
outputVelocityUnits)
```

Description

convertedValues = convvel(*valuesToConvert*, *inputVelocityUnits*, *outputVelocityUnits*) computes the conversion factor from specified input velocity units to specified output velocity units. It then applies the conversion factor to the input to produce the output in the desired units.

Input Arguments

valuesToConvert

Floating-point array of size *m*-by-*n* values that the function is to convert. All values must have the same unit conversions from *inputVelocityUnits* to *outputVelocityUnits*.

inputVelocityUnits

Specified input velocity units. Supported units are:

'ft/s'	Feet per second
'm/s'	Meters per second
'km/s'	Kilometers per second
'in/s'	Inches per second
'km/h'	Kilometers per hour
'mph'	Miles per hour
'kts'	Knots
'ft/min'	Feet per minute

outputVelocityUnits

Specified output velocity units. Supported units are:

'ft/s'	Feet per second
'm/s'	Meters per second
'km/s'	Kilometers per second
'in/s'	Inches per second
'km/h'	Kilometers per hour

'mph'	Miles per hour
'kts'	Knots
'ft/min'	Feet per minute

Output Arguments

convertedValues

Floating-point array of size m -by- n values that the function has converted.

Examples

Convert three velocities from feet per minute to meters per second:

```
a = convvel([30 100 250], 'ft/min', 'm/s')
```

```
a =
```

```
    0.1524    0.5080    1.2700
```

See Also

convacc | convang | convangacc | convangvel | convdensity | convforce | convlength | convmass | convpres | convtemp

Introduced in R2006b

correctairspeed

Convert from one of other two airspeeds to equivalent airspeed (EAS), calibrated airspeed (CAS), or true airspeed (TAS)

Syntax

```
outputAirpseed = correctairspeed(inputAirspeed, speedOfSound, pressure0,
inputAirspeedType, outputAirspeedType)
outputAirpseed = correctairspeed(inputAirspeed, speedOfSound, pressure0,
inputAirspeedType, outputAirspeedType, method)
```

Description

outputAirpseed = correctairspeed(*inputAirspeed*, *speedOfSound*, *pressure0*, *inputAirspeedType*, *outputAirspeedType*) computes the conversion factor from specified input airspeed to specified output airspeed using speed of sound and static pressure. The function applies the conversion factor to the input airspeed to produce the output in the desired airspeed.

outputAirpseed = correctairspeed(*inputAirspeed*, *speedOfSound*, *pressure0*, *inputAirspeedType*, *outputAirspeedType*, *method*) uses the specified method to compute the conversion factor.

Input Arguments

inputAirspeed

Floating-point array of size *m*-by-1 of airspeeds in meters per second. All values must have the same airspeed conversions from *inputAirspeedType* to *outputAirspeedType*.

speedOfSound

Floating-point array of size *m*-by-1 of speeds of sound, in meters per second.

pressure0

Floating-point array of size *m*-by-1 of static air pressures, in pascal.

inputAirspeedType

Input airspeed, specified as a string. Supported airspeeds are:

'TAS'	True airspeed
'CAS'	Calibrated airspeed
'EAS'	Equivalent airspeed

outputAirspeedType

Output airspeed, specified as a string. Supported airspeeds are:

'TAS'	True airspeed
'CAS'	Calibrated airspeed
'EAS'	Equivalent airspeed

method

Specify a method, as a string, for computing the conversion factor.

'TableLookup' (Default) Generate output airspeed by looking up or estimating table values based on inputs *inputAirspeed*, *speedOfSound*, and *pressure0*.

The 'TableLookup' method is not recommended for either of these instances:

- *speedOfSound* less than 200 m/s or greater than 350 m/s.
- *pressure0* less than 1000 Pa or greater than 106,500 Pa.

Using the 'TableLookup' method in these instances causes inaccuracies.

'Equation' Compute output airspeed directly using input values *inputAirspeed*, *speedOfSound*, and *pressure0*.

Calculations involving supersonic airspeeds (greater than Mach 1) require an iterative computation. If the function does not conclude within 30 iterations, it displays an error message.

The `correctairspeed` function automatically uses the 'Equation' method for any of these instances:

- Conversion with *inputAirspeedType* set to 'TAS' and *outputAirspeedType* set to 'EAS'.
- Conversion with *inputAirspeedType* set to 'EAS' and *outputAirspeedType* set to 'TAS'.
- Conversion with *inputAirspeed* is greater than five times the speed of sound at sea level (approximately 1700 m/s).

Output Arguments

outputAirspeed

Floating-point array of size *m*-by-1 of airspeeds in meters per second.

Examples

Convert three airspeeds from true airspeed ('TAS') to equivalent airspeed ('EAS') at 1,000 ms using the 'TableLookup' method:

```
ain = [25.7222; 10.2889; 3.0867];
as = correctairspeed(ain,336.4,89874.6,'TAS','CAS','TableLookup')
as =
```

```
24.5077
 9.8024
 2.9407
```

Convert airspeeds from calibrated airspeed ('CAS') to equivalent airspeed ('EAS') at 1,000 m and 0 m using the 'Equation' method:

```
ain = [25.7222; 10.2889; 3.0867];
sos = [336.4; 340.3; 340.3];
P0 = [ 89874.6; 101325; 101325];
as = correctairspeed(ain,sos,P0,'CAS','EAS','Equation')
as =

    25.7199
    10.2889
     3.0867
```

Convert airspeed from true airspeed ('TAS') to equivalent airspeed ('EAS') at 15,000 meters. Use the `atmoscoesa` function to first calculate the speed of sound (*sos*) and static air pressure (*P0*):

```
ain = 376.25;
[~, sos, P0, ~] = atmoscoesa(15000);
as = correctairspeed( ain, sos, P0, 'EAS', 'TAS')
as =

    946.2572
```

Limitations

This function assumes that air flow is compressible dry air with constant specific heat ratio (γ).

References

Lowry, J.T., *Performance of Light Aircraft*, AIAA Education Series, Washington, D.C., 1999

Aeronautical Vestpocket Handbook, United Technologies Pratt & Whitney, August 1986

Gracey, William, *Measurement of Aircraft Speed and Altitude*, NASA Reference Publication 1046, 1980.

See Also

`airspeed` | `atmoscoesa` | `atmosisa` | `atmoslapse` | `atmosnonstd`

Introduced in R2006b

createBody

Class: Aero.Animation

Package: Aero

Create body and its associated patches in animation

Syntax

```
idx = createBody(h, bodyDataSrc)
idx = h.createBody(bodyDataSrc)
idx = createBody(h, bodyDataSrc, geometrysource)
idx = h.createBody(bodyDataSrc, geometrysource)
```

Description

`idx = createBody(h, bodyDataSrc)` and `idx = h.createBody(bodyDataSrc)` create a new body using the `bodyDataSrc`, makes its patches, and adds it to the animation object `h`. This command assumes a default geometry source type set to `Auto`.

`idx = createBody(h, bodyDataSrc, geometrysource)` and `idx = h.createBody(bodyDataSrc, geometrysource)` create a new body using the `bodyDataSrc` file, makes its patches, and adds it to the animation object `h`. `geometrysource` is the geometry source type for the body.

Input Arguments

<code>bodyDataSrc</code>	Source of data for body.
<code>geometrysource</code>	Geometry source type for body: <ul style="list-style-type: none"> • <code>Auto</code> — Recognizes <code>.mat</code> extensions as MAT-files, <code>.ac</code> extensions as Ac3d files, and structures containing fields of <code>name</code>, <code>faces</code>, <code>vertices</code>, and <code>cdata</code> as MATLAB variables. Default. • <code>Variable</code> — Recognizes structures containing fields of <code>name</code>, <code>faces</code>, <code>vertices</code>, and <code>cdata</code> as MATLAB variables. • <code>MatFile</code> — Recognizes <code>.mat</code> extensions as MAT-files. • <code>Ac3d</code> — Recognizes <code>.ac</code> extensions as Ac3d files. • <code>Custom</code> — Recognizes custom extensions.

Output Arguments

`idx` Index of the body to be created.

Examples

Create a body for the animation object, `h`. Use the Ac3d format data source `pa24-250_orange.ac`, for the body.

```
h = Aero.Animation;  
idx1 = h.createBody('pa24-250_orange.ac', 'Ac3d');
```

Aero.FixedWing.criteriaTable

Class: Aero.FixedWing

Package: Aero

Construct criteria table for fixed-wing static stability analysis

Syntax

```
criteriaTable = Aero.FixedWing.criteriaTable()
```

Description

`criteriaTable = Aero.FixedWing.criteriaTable()` constructs a criteria table for fixed-wing static stability analysis.

Output Arguments

criteriaTable – Criteria table

6-by-*N* table

Criteria table, returned as a 6-by-*N* table where *N* is number of variables. By default, this table appears as follows:

	U	V	W	Alpha	Beta	P	Q	R
FX	"<"	' '	' '	' '	' '	' '	' '	' '
FY	' '	'<'	' '	' '	' '	' '	' '	' '
FZ	' '	' '	'<'	' '	' '	' '	' '	' '
L	' '	' '	' '	' '	' '	'<'	'<'	' '
M	'>'	' '	' '	'<'	' '	' '	'<'	' '
N	' '	' '	' '	' '	'>'	' '	' '	'<'

Examples

Calculate Static Stability of Cessna C182

Calculate the static stability of a Cessna C182.

```
[C182, CruiseState] = astC182();
stability = staticStability(C182, CruiseState)
```

stability =

6×8 table

	U	V	W	Alpha	Beta	P	Q	R
FX	"Stable"	""	""	""	""	""	""	""
FY	""	"Stable"	""	""	""	""	""	""

```
FZ "" "" "Stable" "" "" "" "" ""
L "" "" "" "" "Stable" "Stable" "" ""
M "Stable" "" "" "Stable" "" "" "Stable" ""
N "" "" "" "" "Stable" "" "" "Stable"
```

See Also

`Aero.FixedWing | staticStability`

Introduced in R2021a

datcomimport

Bring DATCOM file into MATLAB environment

Syntax

```
aero = datcomimport(file)
aero = datcomimport(file,usenavar)
aero = datcomimport(file,usenavar,verbose)
aero = datcomimport(file,usenavar,verbose,filetype)
```

Description

`aero = datcomimport(file)` imports aerodynamic data from `file` into `aero`. Before reading the United States Air Force Digital DATCOM file, `datcomimport` initializes values to 99999 when there is not a full set of data for the DATCOM case.

`aero = datcomimport(file,usenavar)` replaces data points with NaN or zero where no DATCOM methods exist or where the method is not applicable.

`aero = datcomimport(file,usenavar,verbose)` displays the status of the DATCOM file being read in the MATLAB Command Window.

`aero = datcomimport(file,usenavar,verbose,filetype)` imports a DATCOM of a particular USAF Digital DATCOM file type.

Examples

Read 1976 Version of Digital DATCOM File

Read the 1976 version Digital DATCOM output file `astdatcom.out`.

```
aero = datcomimport('astdatcom.out')
```

```
aero =
```

```
    1×1 cell array
```

```
    {1×1 struct}
```

Read USAF Digital DATCOM Output File Replacing Data Points with Zeros

Read the 1976 Digital DATCOM output file `astdatcom.out` using zeros to replace data points where no DATCOM methods exist. Use `usenavar` variable to set `usenavar` argument to `false`.

```
usenavar = false;
aero = datcomimport('astdatcom.out',usenavar)
```

```
aero =
```

```
1×1 cell array
{1×1 struct}
```

Read USAF Digital DATCOM Output File Replacing Data Points with Zeroes Specifying Verbose Settings

Read the 1976 Digital DATCOM output file `astdatcom.out` using zeros to replace data points where no DATCOM methods exist and displaying status information in the MATLAB Command Window. Use `usenavar` variable to set `usenav` argument to `false`.

```
usenavar = false;
aero = datcomimport('astdatcom.out',usenavar,1)
```

```
Loading file 'astdatcom.out'.
Reading input data from file 'astdatcom.out'.
Reading output data from file 'astdatcom.out'.
aero =
```

```
1×1 cell array
{1×1 struct}
```

Read USAF Digital DATCOM Output File Replacing Data Points with Zeroes and Specifying Verbose Settings and DATCOM File Type

Read the 1976 Digital DATCOM output file `astdatcom.out` using NaNs to replace data points where no DATCOM methods exist, displaying status information in the MATLAB Command Window, and specifying the DATCOM output file type. Use `usenavar` variable to set `usenav` argument to `true`.

```
usenavar = true;
aero = datcomimport('astdatcom.out',usenavar,1,6)
```

```
Loading file 'astdatcom.out'.
Reading input data from file 'astdatcom.out'.
Reading output data from file 'astdatcom.out'.
aero =
```

```
1×1 cell array
{1×1 struct}
```

Input Arguments

file – DATCOM file

character vector | cell array of file names

Digital DATCOM output file name, specified as a character vector or cell array of file names. This file is generated from USAF Digital DATCOM files.

The `datcomimport` supports only these USAF Digital DATCOM files. You can rename the output files before importing them.

Output File from DATCOM	File Type Versions
for006.dat by all DATCOM versions	1976, 1999, 2007, 2008, 2011, and 2014
for021.dat by DATCOM 2007, DATCOM 2008, DATCOM 2011, and DATCOM 2014	2007, 2008, 2011, and 2014
for042.csv by DATCOM 2008, DATCOM 2011, and DATCOM 2014	2008, 2011, and 2014

Example: for006.dat

Dependencies

The `datcomimport` function accepts DATCOM files of the type specified by the `filetype` argument. By default, the file type is 6 (`for006.dat`, output by all DATCOM versions).

Data Types: `char` | `string`

usenan — Replace data points

`true` (default) | `false`

While importing the DATCOM file, replace data points with NaNs (`true`) or zeroes (`false`) where no DATCOM methods exist or where methods are not applicable.

Data Types: `char` | `string`

verbose — Read status

2 (default) | 0 | 1

Read status of import of DATCOM file, specified as:

- 0 — No status information.
- 1 — Display a status information as a progress bar.
- 2 — Display status information in the MATLAB Command Window.

Data Types: `double`

filetype — DATCOM file type

6 (default) | 2142

DATCOM file type, specified as 6, 21, or 42.

Depending on the file type, the `datcomimport` function expects the imported DATCOM files to contain the fields listed in the **Expected Fields** column.

filetype	Output File from DATCOM	File Type Versions	Expected Fields
6	for006.dat by all DATCOM versions	1976, 1999, 2007, 2008, 2011, and 2014	<ul style="list-style-type: none"> • “Fields for 1976 Version (File Type 6)” on page 4-228 • “Fields for 1999 Version (File Type 6)” on page 4-240 • “Fields for 2007, 2008, 2011, and 2014 Versions (File Type 6)” on page 4-244
21	for021.dat by DATCOM 2007, DATCOM 2008, DATCOM 2011, and DATCOM 2014	2007, 2008, 2011, and 2014	<ul style="list-style-type: none"> • “Fields for 2007, 2008, 2011, and 2014 Versions (File Type 21)” on page 4-248
42	for042.csv by DATCOM 2008, DATCOM 2011, and DATCOM 2014	2008, 2011, and 2014	<ul style="list-style-type: none"> • “Fields for 2008, 2011, and 2014 Version (File Type 42)” on page 4-253

Note If filetype is 21, the function collates the breakpoints and data from all the cases and appends them as the last entry of `aero`.

Data Types: `double`

Output Arguments

`aero` – DATCOM structures

cell array of structures

DATCOM structures, returned as a cell array of structures.

Limitations

- The operational limitations of the 1976 version DATCOM apply to the data contained in AERO. For more information on DATCOM limitations, see “References” on page 4-257, section 2.4.5.
- USAF Digital DATCOM data for wing section, horizontal tail section, vertical tail section, and ventral fin section are not read.

More About

Fields for 1976 Version (File Type 6)

1976 version of file type 6 DATCOM files must contain these fields.

Common Fields for the 1976 Version (File Type 6)

Field	Description	Default
case	Character vector containing the case ID.	[]
mach	Array of Mach numbers.	[]
alt	Array of altitudes.	[]
alpha	Array of angles of attack.	[]
nmach	Number of Mach numbers.	0
nalt	Number of altitudes.	0
nalpha	Number of angles of attack.	0
rnnub	Array of Reynolds numbers.	[]
hypers	Logical denoting, when true, that mach numbers above tsmach are hypersonic. Default values are supersonic.	false
loop	Scalar denoting the type of looping done to generate the DATCOM file. When loop is 1, mach and alt are varied together. When loop is 2, mach varies while alt is fixed. Altitude is then updated and Mach numbers are cycled through again. When loop is 3, mach is fixed while alt varies. mach is then updated and altitudes are cycled through again.	1
sref	Scalar denoting the reference area for the case.	[]
cbar	Scalar denoting the longitudinal reference length.	[]
blref	Scalar denoting the lateral reference length.	[]
dim	Character vector denoting the specified system of units for the case.	'ft'
deriv	Character vector denoting the specified angle units for the case.	'deg'
stmach	Scalar value setting the upper limit of subsonic Mach numbers.	0.6
tsmach	Scalar value setting the lower limit of supersonic Mach numbers.	1.4
save	Logical denoting whether the input values for this case are used in the next case.	false
stype	Scalar denoting the type of asymmetric flap for the case.	[]
trim	Logical denoting the reading of trim data for the case. When trim runs are read, this value is set to true.	false

Field	Description	Default
damp	Logical denoting the reading of dynamic derivative data for the case. When dynamic derivative runs are read, this value is set to <code>true</code> .	false
build	Scalar denoting the reading of build data for the case. When build runs are read, this value is set to 10.	1
part	Logical denoting the reading of partial data for the case. When partial runs are written for each Mach number, this value is set to <code>true</code> .	false
highsym	Logical denoting the reading of symmetric flap high-lift data for the case. When symmetric flap runs are read, this value is set to <code>true</code> .	false
highasy	Logical denoting the reading of asymmetric flap high-lift data for the case. When asymmetric flap runs are read, this value is set to <code>true</code> .	false
highcon	Logical denoting the reading of control/trim tab high-lift data for the case. When control/trim tab runs are read, this value is set to <code>true</code> .	false
tjet	Logical denoting the reading of transverse-jet control data for the case. When transverse-jet control runs are read, this value is set to <code>true</code> .	false
hypeff	Logical denoting the reading of hypersonic flap effectiveness data for the case. When hypersonic flap effectiveness runs are read, this value is set to <code>true</code> .	false
lb	Logical denoting the reading of low aspect ratio wing or lifting body data for the case. When low aspect ratio wing or lifting body runs are read, this value is set to <code>true</code> .	false
pwr	Logical denoting the reading of power effects data for the case. When power effects runs are read, this value is set to <code>true</code> .	false
grnd	Logical denoting the reading of ground effects data for the case. When ground effects runs are read, this value is set to <code>true</code> .	false
wsspn	Scalar denoting the semi-span theoretical panel for wing. This value is used to determine if the configuration contains a canard.	1
hsspn	Scalar denoting the semi-span theoretical panel for horizontal tail. This value is used to determine if the configuration contains a canard.	1

Field	Description	Default
ndelta	Number of control surface deflections: delta, delta1, or deltar.	0
delta	Array of control-surface streamwise deflection angles.	[]
delta1	Array of left lifting surface streamwise control deflection angles, which are defined positive for trailing-edge down.	[]
deltar	Array of right lifting surface streamwise control deflection angles, which are defined positive for trailing-edge down.	[]
ngh	Scalar denoting the number of ground altitudes.	0
grndht	Array of ground heights.	[]
config	Structure of logicals denoting whether the case contains horizontal tails.	false, as follows. <pre>config.downwash = false; config.body = false; config.wing = false; config.htail = false; config.vtail = false; config.vfin = false;</pre>
version	Version of DATCOM file.	1976

Static Longitude and Lateral Stability Fields Available for the 1976 Version (File Type 6)

Field	Matrix of...	Function of...
cd	Drag coefficients, which are defined positive for an aft-acting load.	alpha, mach, alt, build, grndht, delta
cl	Lift coefficients, which are defined positive for an up-acting load.	alpha, mach, alt, build, grndht, delta
cm	Pitching-moment coefficients, which are defined positive for a nose-up rotation.	alpha, mach, alt, build, grndht, delta
cn	Normal-force coefficients, which are defined positive for a normal force in the +Z direction.	alpha, mach, alt, build, grndht, delta
ca	Axial-force coefficients, which are defined positive for a normal force in the +X direction.	alpha, mach, alt, build, grndht, delta
xcp	Distances between moment reference center and the center of pressure divided by the longitudinal reference length. Distances are defined positive for a location forward of the center of gravity.	alpha, mach, alt, build, grndht, delta
cla	Derivatives of lift coefficients relative to alpha.	alpha, mach, alt, build, grndht, delta
cma	Derivatives of pitching-moment coefficients relative to alpha.	alpha, mach, alt, build, grndht, delta
cyb	Derivatives of side-force coefficients relative to sideslip angle.	alpha, mach, alt, build, grndht, delta
cnb	Derivatives of yawing-moment coefficients relative to sideslip angle.	alpha, mach, alt, build, grndht, delta
clb	Derivatives of rolling-moment coefficients relative to sideslip angle.	alpha, mach, alt, build, grndht, delta
qqinf	Ratios of dynamic pressure at the horizontal tail to the freestream value.	alpha, mach, alt, build, grndht, delta
eps	Downwash angle at horizontal tail in degrees.	alpha, mach, alt, build, grndht, delta
depsdalp	Downwash angle relative to angle of attack.	alpha, mach, alt, build, grndht, delta

Dynamic Derivative Fields for the 1976 Version (File Type 6)

Field	Matrix of...	Function of...
clq	Lift force derivatives due to pitch rate.	alpha, mach, alt, build
cmq	Pitching-moment derivatives due to pitch rate.	alpha, mach, alt, build
clad	Lift-force derivatives due to rate of angle of attack.	alpha, mach, alt, build
cmad	Pitching-moment derivatives due to rate of angle of attack.	alpha, mach, alt, build
clp	Rolling-moment derivatives due to roll rate.	alpha, mach, alt, build
cyp	Lateral-force derivatives due to roll rate.	alpha, mach, alt, build
cnp	Yawing-moment derivatives due to roll rate.	alpha, mach, alt, build
cnr	Yawing-moment derivatives due to yaw rate.	alpha, mach, alt, build
clr	Rolling-moment derivatives due to yaw rate.	alpha, mach, alt, build

High-Lift and Control Fields for Symmetric Flaps for the 1976 Version (File Type 6)

Field	Matrix of...	Function of...
dcl_sym	Incremental lift coefficients due to deflection of control surface, valid in the linear-lift angle of attack range.	delta, mach, alt
dcm_sym	Incremental pitching-moment coefficients due to deflection of control surface, valid in the linear-lift angle of attack range.	delta, mach, alt
dclmax_sym	Incremental maximum lift coefficients.	delta, mach, alt
dcdmin_sym	Incremental minimum drag coefficients due to control or flap deflection.	delta, mach, alt
clad_sym	Lift-curve slope of the deflected, translated surface.	delta, mach, alt
cha_sym	Control-surface hinge-moment derivatives due to angle of attack. These derivatives, when defined positive, tend to rotate the flap trailing edge down.	delta, mach, alt
chd_sym	Control-surface hinge-moment derivatives due to control deflection. When defined positive, these derivatives tend to rotate the flap trailing edge down.	delta, mach, alt
dcdi_sym	Incremental induced drag coefficients due to flap deflection.	alpha, delta, mach, alt

High-Lift and Control Fields Available for Asymmetric Flaps for the 1976 Version (File Type 6)

Field	Matrix of...	Function of...
xsc	Streamwise distances from wing leading edge to spoiler tip.	delta, mach, alt
hsc	Projected height of spoiler measured from normal to airfoil meanline.	delta, mach, alt
ddc	Projected height of deflector for spoiler-slot-deflector control.	delta, mach, alt
dsc	Projected height of spoiler control.	delta, mach, alt
clroll	Incremental rolling-moment coefficients due to asymmetrical deflection of control surface. The coefficients are defined positive when right wing is down.	delta, mach, and alt, or alpha, delta, mach, and alt for differential horizontal stabilizer
cn_asy	Incremental yawing-moment coefficients due to asymmetrical deflection of control surface. The coefficients are defined positive when nose is right.	delta, mach, and alt, or alpha, delta, mach, and alt for plain flaps

High-Lift and Control Fields Available for Control/Trim Tabs for the 1976 Version (File Type 6)

Field	Matrix of...	Function of...
fc_con	Stick forces or stick force coefficients.	alpha, delta, mach, alt
fhmcoeff_free	Flap-hinge moment coefficients tab free.	alpha, delta, mach, alt
fhmcoeff_lock	Flap-hinge moment coefficients tab locked.	alpha, delta, mach, alt
fhmcoeff_gear	Flap-hinge moment coefficients due to gearing.	alpha, delta, mach, alt
ttab_def	Trim-tab deflections for zero stick force.	alpha, delta, mach, alt

High-Lift and Control Fields Available for Trim for the 1976 Version (File Type 6)

Field	Matrix of...	Function of...
cl_ustrim	Untrimmed lift coefficients, which are defined positive for an up-acting load.	alpha, mach, alt
cd_ustrim	Untrimmed drag coefficients, which are defined positive for an aft-acting load.	alpha, mach, alt
cm_ustrim	Untrimmed pitching-moment coefficients, which are defined positive for a nose-up rotation.	alpha, mach, alt
delt_trim	Trimmed control-surface streamwise deflection angles.	alpha, mach, alt
dcl_trim	Trimmed incremental lift coefficients in the linear-lift angle of attack range due to deflection of control surface.	alpha, mach, alt
dclmax_trim	Trimmed incremental maximum lift coefficients.	alpha, mach, alt
dcidi_trim	Trimmed incremental induced drag coefficients due to flap deflection.	alpha, mach, alt
dcdmin_trim	Trimmed incremental minimum drag coefficients due to control or flap deflection.	alpha, mach, alt
cha_trim	Trimmed control-surface hinge-moment derivatives due to angle of attack.	alpha, mach, alt
chd_trim	Trimmed control-surface hinge-moment derivatives due to control deflection.	alpha, mach, alt
cl_tailustrim	Untrimmed stabilizer lift coefficients, which are defined positive for an up-acting load.	alpha, mach, alt
cd_tailustrim	Untrimmed stabilizer drag coefficients, which are defined positive for an aft-acting load.	alpha, mach, alt
cm_tailustrim	Untrimmed stabilizer pitching-moment coefficients, which are defined positive for a nose-up rotation.	alpha, mach, alt
hm_tailustrim	Untrimmed stabilizer hinge-moment coefficients, which are defined positive for a stabilizer rotation with leading edge up and trailing edge down.	alpha, mach, alt
aliht_tailtrim	Stabilizer incidence required to trim.	alpha, mach, alt
cl_tailtrim	Trimmed stabilizer lift coefficients, which are defined positive for an up-acting load.	alpha, mach, alt
cd_tailtrim	Trimmed stabilizer drag coefficients, which are defined positive for an aft-acting load.	alpha, mach, alt
cm_tailtrim	Trimmed stabilizer pitching-moment coefficients, which are defined positive for a nose-up rotation.	alpha, mach, alt
hm_tailtrim	Trimmed stabilizer hinge-moment coefficients, which are defined positive for a stabilizer rotation with leading edge up and trailing edge down.	alpha, mach, alt
cl_trimi	Lift coefficients at trim incidence. These coefficients are defined positive for an up-acting load.	alpha, mach, alt

Field	Matrix of...	Function of...
cd_trimi	Drag coefficients at trim incidence. These coefficients are defined positive for an aft-acting load.	alpha, mach, alt

Transverse Jet Control Fields for the 1976 Version (File Type 6)

Field	Description	Stored with Indices of...
time	Matrix of times.	mach, alt, alpha
ctrlfrc	Matrix of control forces.	mach, alt, alpha
locmach	Matrix of local Mach numbers.	mach, alt, alpha
reynum	Matrix of Reynolds numbers.	mach, alt, alpha
locpres	Matrix of local pressures.	mach, alt, alpha
dynpres	Matrix of dynamic pressures.	mach, alt, alpha
blayer	Cell array of character vectors containing the state of the boundary layer.	mach, alt, alpha
ctrlcoeff	Matrix of control force coefficients.	mach, alt, alpha
corrcoeff	Matrix of corrected force coefficients.	mach, alt, alpha
sonicamp	Matrix of sonic amplification factors.	mach, alt, alpha
ampfact	Matrix of amplification factors.	mach, alt, alpha
vacthr	Matrix of vacuum thrusts.	mach, alt, alpha
minpres	Matrix of minimum pressure ratios.	mach, alt, alpha
minjet	Matrix of minimum jet pressures.	mach, alt, alpha
jetpres	Matrix of jet pressures.	mach, alt, alpha
massflow	Matrix of mass flow rates.	mach, alt, alpha
propelwt	Matrix of propellant weights.	mach, alt, alpha

Hypersonic Fields for the 1976 Version (File Type 6)

Field	Matrix of...	Stored with Indices of...
df_normal	Increments in normal force per spanwise foot of control.	alpha, delta, mach
df_axial	Increments in axial force per spanwise foot of control.	alpha, delta, mach
cm_normal	Increments in pitching moment due to normal force per spanwise foot of control.	alpha, delta, mach
cm_axial	Increments in pitching moment due to axial force per spanwise foot of control.	alpha, delta, mach
cp_normal	Center of pressure locations of normal force.	alpha, delta, mach
cp_axial	Center of pressure locations of axial force.	alpha, delta, mach

Auxiliary and Partial Fields Available for the 1976 Version (File Type 6)

Field	Matrix of...	Stored with Indices of...
wetarea_b	Body wetted area.	mach, alt, number of runs
xcg_b	Longitudinal locations of the center of gravity.	mach, alt, number of runs (normally 1, 2 for hypers = true)
zcg_b	Vertical locations of the center of gravity.	mach, alt, number of runs (normally 1, 2 for hypers = true)
basearea_b	Body base area.	mach, alt, number of runs (normally 1, 2 for hypers = true)
cd0_b	Body zero lift drags.	mach, alt, number of runs (normally 1, 2 for hypers = true)
basedrag_b	Body base drags.	mach, alt, number of runs (normally 1, 2 for hypers = true)
fricdrag_b	Body friction drags.	mach, alt, number of runs (normally 1, 2 for hypers = true)
presdrag_b	Body pressure drags.	mach, alt, number of runs (normally 1, 2 for hypers = true)
lemac	Leading edge mean aerodynamic chords.	mach, alt
sidewash	sidewash	mach, alt
hiv_b_w	iv-b(w)	alpha, mach, alt
hiv_w_h	iv-w(h)	alpha, mach, alt
hiv_b_h	iv-b(h)	alpha, mach, alt
gamma	$\gamma * 2 * \pi * \alpha * v * r$	alpha, mach, alt
gamma2pialpvr	$\gamma * (2 * \pi * \alpha * v * r) * t$	alpha, mach, alt
clpgammacl0	$cl_p(\gamma = cl = 0)$	mach, alt
clpgammaclp	$cl_p(\gamma) / cl(\gamma = 0)$	mach, alt
cnptheta	cnp/theta	mach, alt
cypgamma	cyp/gamma	mach, alt
cypcl	cyp/cl (cl=0)	mach, alt
clbgamma	clb/gamma	mach, alt
cmotheta_w	(cmo/theta)w	mach, alt
cmotheta_h	(cmo/theta)h	mach, alt
espeff	(epsoln)eff	alpha, mach, and alt
despdalpeff	d(epsoln)/d(alpha) eff	alpha, mach, alt
dragdiv	drag divergence mach number	mach, alt
cd0mach	Four Mach numbers for the zero lift drag.	index, mach, alt
cd0	Four zero lift drags.	index, mach, alt
clbclmfb_****	(clb/cl)mfb, where **** is either wb (wing-body) or bht (body-horizontal tail).	mach, alt.

Field	Matrix of...	Stored with Indices of...
cnam14_****	(cna)m=1.4, where **** is either wb (wing-body) or bht (body-horizontal tail).	mach,alt
area_ *_ **	Areas, where * is either w (wing), ht (horizontal tail), vt (vertical tail), or vf (ventral fin) and ** is either tt (total theoretical), ti (theoretical inboard), te (total exposed), ei (exposed inboard), or o (outboard).	mach, alt, number of runs (normally 1, 2 for hypers = true)
taperratio_ *_ **	Taper ratios, where * is either w (wing), ht (horizontal tail), vt (vertical tail), or vf (ventral fin) and ** is either tt (total theoretical), ti (theoretical inboard), te (total exposed), ei (exposed inboard), or o (outboard).	mach, alt, number of runs (normally 1, 2 for hypers = true)
aspectratio_ *_ **	Aspect ratios, where * is either w (wing), ht (horizontal tail), vt (vertical tail), or vf (ventral fin) and ** is either tt (total theoretical), ti (theoretical inboard), te (total exposed), ei (exposed inboard), or o (outboard).	mach, alt, number of runs (normally 1, 2 for hypers = true)
qcsweep_ *_ **	Quarter chord sweeps, where * is either w (wing), ht (horizontal tail), vt (vertical tail), or vf (ventral fin) and ** is either tt (total theoretical), ti (theoretical inboard), te (total exposed), ei (exposed inboard), or o (outboard).	mach, alt, number of runs (normally 1, 2 for hypers = true)
mac_ *_ **	Mean aerodynamic chords, where * is either w (wing), ht (horizontal tail), vt (vertical tail), or vf (ventral fin) and ** is either tt (total theoretical), ti (theoretical inboard), te (total exposed), ei (exposed inboard), or o (outboard).	mach, alt, number of runs (normally 1, 2 for hypers = true)
qcmac_ *_ **	Quarter chord x (mac), where * is either w (wing), ht (horizontal tail), vt (vertical tail), or vf (ventral fin) and ** is either tt (total theoretical), ti (theoretical inboard), te (total exposed), ei (exposed inboard), or o (outboard).	mach, alt, number of runs (normally 1, 2 for hypers = true)
ymac_ *_ **	y(mac), where * is either w (wing), ht (horizontal tail), vt (vertical tail), or vf (ventral fin) and ** is either tt (total theoretical), ti (theoretical inboard), te (total exposed), ei (exposed inboard), or o (outboard).	mach, alt, number of runs (normally 1, 2 for hypers = true)

Field	Matrix of...	Stored with Indices of...
cd0_*_**	Zero lift drags, where * is either w (wing), ht (horizontal tail), vt (vertical tail), or vf (ventral fin) and ** is either tt (total theoretical), ti (theoretical inboard), te (total exposed), ei (exposed inboard), or o (outboard).	mach, alt, number of runs (normally 1, 2 for hypers = true)
friccoeff_*_**	Friction coefficients, where * is either w (wing), ht (horizontal tail), vt (vertical tail), or vf (ventral fin) and ** is either tt (total theoretical), ti (theoretical inboard), te (total exposed), ei (exposed inboard), or o (outboard).	mach, alt, number of runs (normally 1, 2 for hypers = true)
cla_b_***	cla-b(***), where *** is either w (wing) or ht (stabilizer).	mach, alt, number of runs (normally 1, 2 for hypers = true)
cla_***_b	cla-***(b), where *** is either w (wing) or ht (stabilizer).	mach, alt, number of runs (normally 1, 2 for hypers = true)
k_b_***	k-b(***), where *** is either w (wing) or ht (stabilizer).	mach, alt, number of runs (normally 1, 2 for hypers = true)
k_***_b	k-***(b), where *** is either w (wing) or ht (stabilizer).	mach, alt, number of runs (normally 1, 2 for hypers = true)
xacc_b_***	xac/c-b(***), where *** is either w (wing) or ht (stabilizer).	mach, alt, number of runs (normally 1, 2 for hypers = true)
cdlcl2_***	cdl/cl ² , where *** is either w (wing) or ht (stabilizer).	mach, alt
clbcl_***	clb/cl, where *** is either w (wing) or ht (stabilizer).	mach, alt
fmach0_***	Force break Mach numbers with zero sweep, where *** is either w (wing) or ht (stabilizer).	mach, alt
fmach_***	Force break Mach numbers with sweep, where *** is either w (wing) or ht (stabilizer).	mach, alt
macha_***	mach(a), where *** is either w (wing) or ht (stabilizer).	mach, alt
machb_***	mach(b), where *** is either w (wing) or ht (stabilizer).	mach, alt
claa_***	cla(a), where *** is either w (wing) or ht (stabilizer).	mach, alt
clab_***	cla(b), where *** is either w (wing) or ht (stabilizer).	mach, alt
clbm06_***	(clb/cl) _{m=0.6} , where *** is either w (wing) or ht (stabilizer).	mach, alt
clbm14_***	(clb/cl) _{m=1.4} , where *** is either w (wing) or ht (stabilizer).	mach, alt

Field	Matrix of...	Stored with Indices of...
clalpmach_***	Five Mach numbers for the lift curve slope, where *** is either w (wing) or ht (stabilizer).	index, mach, alt
clalp_***	Five lift-curve slope values, where *** is either w (wing) or ht (stabilizer).	index, mach, alt

Fields for 1999 Version (File Type 6)

1999 version of file type 6 DATCOM files must contain these fields.

Common Fields for the 1999 Version (File Type 6)

Field	Description	Default
case	Character vector containing the case ID.	[]
mach	Array of Mach numbers.	[]
alt	Array of altitudes.	[]
alpha	Array of angles of attack.	[]
nmach	Number of Mach numbers.	0
nalt	Number of altitudes.	1
nalpha	Number of angles of attack.	0
rnnub	Array of Reynolds numbers.	[]
beta	Scalar containing sideslip angle.	0
phi	Scalar containing aerodynamic roll angle.	0
loop	Scalar denoting the type of looping performed to generate the DATCOM file. When <code>loop</code> is 1, <code>mach</code> and <code>alt</code> are varied together. The only loop option for the 1999 version of DATCOM is <code>loop</code> is equal to 1.	1
sref	Scalar denoting the reference area for the case.	[]
cbar	Scalar denoting the longitudinal reference length.	[]
blref	Scalar denoting the lateral reference length.	[]
dim	Character vector denoting the specified system of units for the case.	'ft'
deriv	Character vector denoting the specified angle units for the case.	'deg'
save	Logical denoting whether the input values for this case are used in the next case.	false
stype	Scalar denoting the type of asymmetric flap for the case.	[]
trim	Logical denoting the reading of trim data for the case. When trim runs are read, this value is set to <code>true</code> .	false
damp	Logical denoting the reading of dynamic derivative data for the case. When dynamic derivative runs are read, this value is set to <code>true</code> .	false
build	Scalar denoting the reading of build data for the case. When build runs are read, this value is set to the number of build runs depending on the vehicle configuration.	1
part	Logical denoting the reading of partial data for the case. When partial runs are written for each Mach number, this value is set to <code>true</code> .	false

Field	Description	Default
hypreff	Logical denoting the reading of hypersonic data for the case. When hypersonic data is read, this value is set to <code>true</code> .	<code>false</code>
ngh	Scalar denoting the number of ground altitudes.	<code>0</code>
nolat	Logical denoting the calculation of the lateral-direction derivatives is inhibited.	<code>false</code>
config	Structure of logicals and structures detailing the case configuration and fin deflections.	<code>config.body = false</code> <code>config.fin1.avail = false;</code> <code>config.fin1.npanel = [];</code> <code>config.fin1.delta = [];</code> <code>config.fin2.avail = false;</code> <code>config.fin2.npanel = [];</code> <code>config.fin2.delta = [];</code> <code>config.fin3.avail = false;</code> <code>config.fin3.npanel = [];</code> <code>config.fin3.delta = [];</code> <code>config.fin4.avail = false;</code> <code>config.fin4.npanel = [];</code> <code>config.fin4.delta = [];</code>
version	Version of DATCOM file.	<code>1999</code>

Static Longitude and Lateral Stability Fields Available for the 1999 Version (File Type 6)

Field	Matrix of...	Function of...
cd	Drag coefficients, which are defined positive for an aft-acting load.	alpha, mach, alt, build
cl	Lift coefficients, which are defined positive for an up-acting load.	alpha, mach, alt, build
cm	Pitching-moment coefficients, which are defined positive for a nose-up rotation.	alpha, machalt, build
cn	Normal-force coefficients, which are defined positive for a normal force in the +Z direction.	alpha, mach, alt, build
ca	Axial-force coefficients, which are defined positive for a normal force in the +X direction.	alpha, mach, alt, build
xcp	Distances between moment reference center and the center of pressure divided by the longitudinal reference length. These distances are defined positive for a location forward of the center of gravity.	alpha, mach, alt, build
cna	Derivatives of normal-force coefficients relative to alpha.	alpha, mach, alt, build
cma	Derivatives of pitching-moment coefficients relative to alpha.	alpha, mach, alt, build
cyb	Derivatives of side-force coefficients relative to sideslip angle.	alpha, mach, alt, build
cnb	Derivatives of yawing-moment coefficients relative to sideslip angle.	alpha, mach, alt, build
clb	Derivatives of rolling-moment coefficients relative to sideslip angle.	alpha, mach, alt, build
clod	Ratios of lift coefficient to drag coefficient.	alpha, mach, alt, build
cy	Side-force coefficients.	alpha, mach, alt, build
cln	Yawing-moment coefficient in body-axis.	alpha, mach, alt, build
cll	Rolling-moment coefficient in body-axis.	alpha, mach, alt, build

Dynamic Derivative Fields for the 1999 Version (File Type 6)

Field	Matrix of...	Function of...
cnq	Normal-force derivatives due to pitch rate.	alpha, mach, alt, build
cmq	Pitching-moment derivatives due to pitch rate.	alpha, mach, alt, build
caq	Axial-force derivatives due to pitch rate.	alpha, mach, alt, build
cnad	Normal-force derivatives due to rate of angle of attack.	alpha, mach, alt, build
cmad	Pitching-moment derivatives due to rate of angle of attack.	alpha, mach, alt, build
clp	Rolling-moment derivatives due to roll rate.	alpha, mach, alt, build
cyp	Lateral force derivatives due to roll rate.	alpha, mach, alt, build
cnp	Yawing-moment derivatives due to roll rate.	alpha, mach, alt, build
cnr	Yawing-moment derivatives due to yaw rate.	alpha, mach, alt, build
clr	Rolling-moment derivatives due to yaw rate.	alpha, mach, alt, build
cyr	Side force derivatives due to yaw rate.	alpha, mach, alt, build

Fields for 2007, 2008, 2011, and 2014 Versions (File Type 6)

2007, 2008, 2011, and 2014 versions of file type 6 DATCOM files must contain these fields.

Common Fields for the 2007, 2008, 2011, and 2014 Versions (File Type 6)

Field	Description	Default
case	Character vector containing the case ID.	[]
mach	Array of Mach numbers.	[]
alt	Array of altitudes.	[]
alpha	Array of angles of attack.	[]
nmach	Number of Mach numbers.	0
nalt	Number of altitudes.	1
nalpha	Number of angles of attack.	0
rnnub	Array of Reynolds numbers.	[]
beta	Scalar containing sideslip angle. Note This value does not appear correctly for the 2014 version. It always displays 0.	0
phi	Scalar containing aerodynamic roll angle.	0
loop	Scalar denoting the type of looping performed to generate the DATCOM file. When loop is 1, mach and alt are varied together. The only loop option for the 2007 version of DATCOM is loop, equal to 1.	1
sref	Scalar denoting the reference area for the case.	[]
cbar	Scalar denoting the longitudinal reference length.	[]
blref	Scalar denoting the lateral reference length.	[]
dim	Character vector denoting the specified system of units for the case.	'ft'
deriv	Character vector denoting the specified angle units for the case.	'deg'
save	Logical denoting whether the input values for this case are used in the next case.	false
stype	Scalar denoting the type of asymmetric flap for the case.	[]
trim	Logical denoting the reading of trim data for the case. When trim runs are read, this value is set to true.	false
damp	Logical denoting the reading of dynamic derivative data for the case. When dynamic derivative runs are read, this value is set to true.	false

Field	Description	Default
build	Scalar denoting the reading of build data for the case. When build runs are read, this value is set to the number of build runs depending on the vehicle configuration.	1
part	Logical denoting the reading of partial data for the case. When partial runs are written for each Mach number, this value is set to <code>true</code> .	false
hypeff	Logical denoting the reading of hypersonic data for the case. When hypersonic data is read, this value is set to <code>true</code> .	false
ngh	Scalar denoting the number of ground altitudes.	0
nolat	Logical denoting the calculation of the lateral-direction derivatives is inhibited.	false
config	Structure of logicals and structures detailing the case configuration and fin deflections.	<pre> config.body = false; config.fin1.avail = false; config.fin1.npanel = []; config.fin1.delta = []; config.fin2.avail = false; config.fin2.npanel = []; config.fin2.delta = []; config.fin3.avail = false; config.fin3.npanel = []; config.fin3.delta = []; config.fin4.avail = false; config.fin4.npanel = []; config.fin4.delta = []; </pre>
nolat_ - namelist	Logical denoting the calculation of the lateral-direction derivatives is inhibited in the DATCOM input case.	false
version	Version of DATCOM file.	2007

**Static Longitude and Lateral Stability Fields Available for the 2007, 2008, 2011, and 2014 Versions
(File Type 6)**

Field	Matrix of...	Function of...
cd	Drag coefficients, which are defined positive for an aft-acting load.	alpha, mach, alt, build
cl	Lift coefficients, which are defined positive for an up-acting load.	alpha, mach, alt, build
cm	Pitching-moment coefficients, which are defined positive for a nose-up rotation.	alpha, mach, alt, build
cn	Normal-force coefficients, which are defined positive for a normal force in the +Z direction.	alpha, mach, alt, build
ca	Axial-force coefficients, which are defined positive for a normal force in the +X direction.	alpha, mach, alt, build
xcp	Distances between moment reference center and the center of pressure divided by the longitudinal reference length. These distances are defined positive for a location forward of the center of gravity.	alpha, mach, alt, build
cna	Derivatives of normal-force coefficients relative to alpha.	alpha, mach, alt, build
cma	Derivatives of pitching-moment coefficients relative to alpha.	alpha, mach, alt, build
cyb	Derivatives of side-force coefficients relative to sideslip angle.	alpha, mach, alt, build
cnb	Derivatives of yawing-moment coefficients relative to sideslip angle.	alpha, mach, alt, build
clb	Derivatives of rolling-moment coefficients relative to sideslip angle.	alpha, mach, alt, build
clod	Ratios of lift coefficient to drag coefficient.	alpha, mach, alt, build
cy	Side-force coefficients.	alpha, mach, alt, build
cln	Yawing-moment coefficient in body-axis.	alpha, mach, alt, build
cll	Rolling-moment coefficient in body-axis.	alpha, mach, alt, build

Dynamic Derivative Fields for the 2007, 2008, 2011, and 2014 Versions (File Type 6)

Field	Matrix of...	Function of...
cnq	Normal-force derivatives due to pitch rate.	alpha, mach, alt, build
cmq	Pitching-moment derivatives due to pitch rate.	alpha, mach, alt, build
caq	Axial-force derivatives due to pitch rate.	alpha, mach, alt, build
cnad	Normal-force derivatives due to rate of angle of attack.	alpha, mach, alt, build
cmad	Pitching-moment derivatives due to rate of angle of attack.	alpha, mach, alt, build
clp	Rolling-moment derivatives due to roll rate.	alpha, mach, alt, build
cyp	Lateral-force derivatives due to roll rate.	alpha, mach, alt, build
cnp	Yawing-moment derivatives due to roll rate.	alpha, mach, alt, build
cnr	Yawing-moment derivatives due to yaw rate.	alpha, mach, alt, build
clr	Rolling-moment derivatives due to yaw rate	alpha, mach, alt, build
cyr	Side-force derivatives due to yaw rate.	alpha, mach, alt, build

Fields for 2007, 2008, 2011, and 2014 Versions (File Type 21)

2007, 2008, 2011, and 2014 versions of file type 21 DATCOM files must contain these fields.

Common Fields for the 2007, 2008, 2011, and 2014 Versions (File Type 21)

Field	Description	Default
mach	Array of Mach numbers.	[]
alt	Array of altitudes.	[]
alpha	Array of angles of attack.	[]
nalpha	Number of angles of attack.	0
beta	Scalar containing sideslip angle. Note This value does not appear correctly for the 2014 version. It always displays 0.	0
total_col	Scalar denoting the type of looping performed to generate the DATCOM file. When <code>loop</code> is 1, <code>mach</code> and <code>alt</code> are varied together. The only loop option for the 2007, 2008, 2011, and 2014 versions of DATCOM is <code>loop</code> equal to 1.	[]
deriv_col	Logical denoting the calculation of the lateral-direction derivatives is inhibited.	0
config	Structure of logicals and structures detailing the case configuration and fin deflections.	<code>config.fin1.delta = zeros(1,8);</code> <code>config.fin2.delta = zeros(1,8);</code> <code>config.fin3.delta = zeros(1,8);</code> <code>config.fin4.delta = zeros(1,8);</code>
version	Version of DATCOM file.	2007

Static Longitude and Lateral Stability Fields Available for the 2007, 2008, 2011, and 2014 Versions (File Type 21)

Field	Matrix of...	Function of...
cn	Normal-force coefficients, which are defined positive for a normal force in the +Z direction.	alpha, mach, alt, beta, config.fin1.delta, config.fin2.delta, config.fin3.delta, config.fin4.delta
cm	Pitching-moment coefficients, which are defined positive for a nose-up rotation.	alpha, mach, alt, beta, config.fin1.delta, config.fin2.delta, config.fin3.delta, config.fin4.delta
ca	Axial-force coefficients, which are defined positive for a normal force in the +X direction.	alpha, mach, alt, beta, config.fin1.delta, config.fin2.delta, config.fin3.delta, config.fin4.delta
cy	Side-force coefficients.	alpha, mach, alt, beta, config.fin1.delta, config.fin2.delta, config.fin3.delta, config.fin4.delta
cln	Yawing-moment coefficient in body-axis.	alpha, mach, alt, beta, config.fin1.delta, config.fin2.delta, config.fin3.delta, config.fin4.delta
cll	Rolling-moment coefficient in body-axis.	alpha, mach, alt, beta, config.fin1.delta, config.fin2.delta, config.fin3.delta, config.fin4.delta

Dynamic Derivative Fields for the 2007, 2008, 2011, and 2014 Versions (File Type 21)

Field	Matrix of...	Function of...
cnad	Normal-force derivatives due to rate of angle of attack.	alpha, mach, alt, beta, config.fin1.delta, config.fin2.delta, config.fin3.delta, config.fin4.delta
cmad	Pitching-moment derivatives due to rate of angle of attack.	alpha, mach, alt, beta, config.fin1.delta, config.fin2.delta, config.fin3.delta, config.fin4.delta
cnq	Normal-force derivatives due to pitch rate.	alpha, mach, alt, beta, config.fin1.delta, config.fin2.delta, config.fin3.delta, config.fin4.delta
cmq	Pitching-moment derivatives due to pitch rate.	alpha, mach, alt, beta, config.fin1.delta, config.fin2.delta, config.fin3.delta, config.fin4.delta
caq	Axial-force derivatives due to pitch rate.	alpha, mach, alt, beta, config.fin1.delta, config.fin2.delta, config.fin3.delta, config.fin4.delta
cyq	Side-force due to pitch rate.	alpha, mach, alt, beta, config.fin1.delta, config.fin2.delta, config.fin3.delta, config.fin4.delta
clnq	Yawing-moment due to pitch rate.	alpha, mach, alt, beta, config.fin1.delta, config.fin2.delta, config.fin3.delta, config.fin4.delta
cllq	Rolling-moment due to pitch rate.	alpha, mach, alt, beta, config.fin1.delta, config.fin2.delta, config.fin3.delta, config.fin4.delta
cnp	Yawing-moment derivatives due to roll rate.	alpha, mach, alt, beta, config.fin1.delta, config.fin2.delta, config.fin3.delta, config.fin4.delta

Field	Matrix of...	Function of...
cap	Axial-force due to roll rate.	alpha, mach, alt, beta, config.fin1.delta, config.fin2.delta, config.fin3.delta, config.fin4.delta
cyp	Lateral-force derivatives due to roll rate.	alpha, mach, alt, beta, config.fin1.delta, config.fin2.delta, config.fin3.delta, config.fin4.delta
clnp	Yawing-moment due to roll rate.	alpha, mach, alt, beta, config.fin1.delta, config.fin2.delta, config.fin3.delta, config.fin4.delta
cllp	Rolling-moment due to roll rate.	alpha, mach, alt, beta, config.fin1.delta, config.fin2.delta, config.fin3.delta, config.fin4.delta
cnr	Yawing-moment derivatives due to yaw rate.	alpha, mach, alt, beta, config.fin1.delta, config.fin2.delta, config.fin3.delta, config.fin4.delta
car	Axial-force due to yaw rate.	alpha, mach, alt, beta, config.fin1.delta, config.fin2.delta, config.fin3.delta, config.fin4.delta
cyr	Side-force derivatives due to yaw rate.	alpha, mach, alt, beta, config.fin1.delta, config.fin2.delta, config.fin3.delta, config.fin4.delta
clnr	Yawing-moment due to yaw rate.	alpha, mach, alt, beta, config.fin1.delta, config.fin2.delta, config.fin3.delta, config.fin4.delta
cllr	Rolling-moment due to yaw rate.	alpha, mach, alt, beta, config.fin1.delta, config.fin2.delta, config.fin3.delta, config.fin4.delta

Fields for 2008, 2011, and 2014 Version (File Type 42)

2008, 2011, and 2014 versions of file type 42 DATCOM files must contain these fields.

Fields for the 2008, 2011, and 2014 Version (File Type 42)

Field	Description	Default
case	Character vector containing the case ID.	[]
totalCol	Scalar containing number of columns of data in file.	[]
mach	Array of Mach numbers.	[]
alt	Array of altitudes.	[]
alpha	Array of angles of attack.	[]
nmach	Number of Mach numbers.	0
nalpha	Number of angles of attack.	0
rnnub	Array of Reynolds numbers.	[]
q	Dynamic pressure.	[]
beta	Scalar containing sideslip angle. Note This value does not appear correctly for the 2014 version. It always displays 0.	0
phi	Scalar containing aerodynamic roll angle.	0
sref	Scalar denoting the reference area for the case.	[]
cbar	Scalar denoting the longitudinal reference length.	[]
blref	Scalar denoting the lateral reference length.	[]
xcg	Distance from nose to center of gravity.	[]
xmrp	Distance from nose to center of gravity, measured in calibers.	[]
deriv	Character vector denoting the specified angle units for the case.	'deg'
trim	Logical denoting the reading of trim data for the case. When trim runs are read, this value is set to true.	false
damp	Logical denoting the reading of dynamic derivative data for the case. When dynamic derivative runs are read, this value is set to true.	false
build	Scalar denoting the reading of partial data for the case. This value is set to the number of partial runs depending on the vehicle configuration.	1
part	Logical denoting the reading of partial data for the case. When partial runs are written for each Mach number, this value is set to true.	false

Field	Description	Default
nolat	Logical denoting the calculation of the lateral-direction derivatives is inhibited.	true
config	Structure of logicals and structures detailing the case configuration and fin deflections.	<pre>config.body = false; config.fin1.avail = false; config.fin1.npanel = []; config.fin1.delta = []; config.fin2.avail = false; config.fin2.npanel = []; config.fin2.delta = []; config.fin3.avail = false; config.fin3.npanel = []; config.fin3.delta = []; config.fin4.avail = false; config.fin4.npanel = [];</pre>
version	Version of DATCOM file.	2008

Static Longitude and Lateral Stability Fields Available for the 2008, 2011, and 2014 Versions (File Type 42)

Field	Matrix of...	Function of...
delta	Trim deflection angles.	alpha, mach
cd	Drag coefficients, which are defined positive for an aft-acting load.	alpha, mach, build
cl	Lift coefficients, which are defined positive for an up-acting load.	alpha, mach, build
cm	Pitching-moment coefficients, which are defined positive for a nose-up rotation.	alpha, mach, build
cn	Normal-force coefficients, which are defined positive for a normal force in the +Z direction.	alpha, mach, build
ca	Axial-force coefficients, which are defined positive for a normal force in the +X direction.	alpha, mach, build
caZeroBase	Axial-force coefficient with no base drag included.	alpha, mach, build
caFullBase	Axial-force coefficient with full base drag included.	alpha, mach, build
xcp	Distance from nose to center of pressure.	alpha, mach, build
cna	Derivatives of normal-force coefficients relative to alpha.	alpha, mach, build
cma	Derivatives of pitching-moment coefficients relative to alpha.	alpha, mach, build
cyb	Derivatives of side-force coefficients relative to sideslip angle.	alpha, mach, build
cnb	Derivatives of yawing-moment coefficients relative to sideslip angle.	alpha, mach, build
clb	Derivatives of rolling-moment coefficients relative to sideslip angle.	alpha, mach, build
clod	Ratios of lift coefficient to drag coefficient.	alpha, mach, build
cy	Side-force coefficient.	alpha, mach, build
cln	Yawing-moment coefficient.	alpha, mach, build
cll	Rolling-moment coefficient.	alpha, mach, build

Dynamic Derivative Fields for the 2008, 2011, and 2014 Version (File Type 42)

Field	Matrix of...	Function of...
cnq	Normal-force derivatives due to pitch rate.	alpha, mach, alt, build
cmq	Pitching-moment derivatives due to pitch rate.	alpha, mach, alt, build
caq	Axial-force derivatives due to pitch rate.	alpha, mach, alt, build
cnad	Normal-force derivatives due to rate of angle of attack.	alpha, mach, alt, build
cmad	Pitching-moment derivatives due to rate of angle of attack.	alpha, mach, alt, build
cyq	Lateral-force derivatives due to pitch rate.	alpha, mach, alt, build
clnq	Yawing-moment derivatives due to pitch rate.	alpha, mach, alt, build
cllq	Rolling-moment derivatives due to pitch rate.	alpha, mach, alt, build
cyr	Side-force derivatives due to yaw rate.	alpha, mach, alt, build
clnr	Yawing-moment derivatives due to yaw rate.	alpha, mach, alt, build
cllr	Rolling-moment derivatives due to yaw rate.	alpha, mach, alt, build
cyp	Lateral-force derivatives due to roll rate.	alpha, mach, alt, build
clnp	Yawing-moment derivatives due to roll rate.	alpha, mach, alt, build
cllp	Rolling-moment derivatives due to roll rate.	alpha, mach, alt, build
cnp	Normal-force derivatives due to roll rate.	alpha, mach, alt, build
cmp	Pitching-moment derivatives due to roll rate.	alpha, mach, alt, build
cap	Axial-force derivatives due to roll rate.	alpha, mach, alt, build
cnr	Normal-force derivatives due to yaw rate.	alpha, mach, alt, build
cmr	Pitching-moment derivatives due to roll rate.	alpha, mach, alt, build
car	Axial-force derivatives due to yaw rate.	alpha, mach, alt, build

References

- [1] AFFDL-TR-79-3032: *The USAF Stability and Control DATCOM*, Volume 1, User's Manual
- [2] AFRL-VA-WP-TR-1998-3009: *MISSILE DATCOM*, User's Manual - 1997 FORTRAN 90 Revision
- [3] AFRL-RB-WP-TR-2009-3015: *MISSILE DATCOM*, User's Manual - 2008 Revision
- [4] AFRL-RB-WP-TR-2011-3071: *MISSILE DATCOM*, User's Manual - 2011 Revision
- [5] AFRL-RQ-WP-TR-2014-3999: *MISSILE DATCOM*, Users Manual - 2014 Revision

See Also**Topics**

"Importing from USAF Digital DATCOM Files" on page 5-2

Introduced in R2006b

datcomToFixedWing

Class: Aero.FixedWing

Package: Aero

Construct fixed-wing aircraft from Digital DATCOM structure

Syntax

```
aircraft = datcomToFixedWing(aircraft,datcomstruct)
[aircraft,state] = datcomToFixedWing(aircraft,datcomstruct)
[aircraft,state] = datcomToFixedWing( ____,Name,Value)
```

Description

`aircraft = datcomToFixedWing(aircraft,datcomstruct)` returns a modified fixed-wing aircraft, `aircraft`, constructed from the fields of a Digital DATCOM structure, `datcomstruct`. To create a DATCOM structure, see `datcomimport`.

`[aircraft,state] = datcomToFixedWing(aircraft,datcomstruct)` returns an array of `Aero.FixedWing.State` objects in addition to the modified fixed-wing aircraft..

`[aircraft,state] = datcomToFixedWing(____,Name,Value)` returns the modified fixed-wing aircraft using additional options specified by one or more `Name,Value` pair arguments. Specify the `Name,Value` argument as the last input argument followed by the input argument combination in the previous syntax.

Input Arguments

aircraft — Aero.FixedWing aircraft

scalar

Aero.FixedWing aircraft, specified as a scalar. To construct an empty aircraft, use `Aero.FixedWing(0)`.

datcomstruct — Digital DATCOM structure

scalar

Digital DATCOM structure, specified as a scalar. To create the digital DATCOM structure, use the `datcomimport` function.

Name-Value Pair Arguments

Specify optional comma-separated pairs of `Name,Value` arguments. `Name` is the argument name and `Value` is the corresponding value. `Name` must appear inside quotes. You can specify several name and value pair arguments in any order as `Name1,Value1,...,NameN,ValueN`.

Example: 'StateMode','Exhaustive'

Build — Build run dimension

scalar

Build run dimension to use, specified as a scalar greater than or equal to 1 or less than or equal to `datcomStruct.build`. The default is the value of `datcomStruct.build`.

Data Types: `double`

Atmosphere — Standard atmosphere model

'ISA' (default) | 'COESA'

Standard atmosphere model when calculating the environment properties temperature, pressure, speed of sound, density, and aircraft speed, specified as 'ISA' or 'COESA'.

Data Types: `char` | `string`

StateMode — Source for constructing aircraft states

'Scalar' (default) | 'Exhaustive'

Source for constructing aircraft states, specified as

- 'Scalar' — `datcomToFixedWing` returns a scalar template state with the unit systems and control names derived from the DATCOM file. All other state fields retain their default values.
- 'Exhaustive' — All supported fields from the DATCOM file are combined in an exhaustive state array. This option might take several minutes to execute.

Data Types: `char` | `string`

Output Arguments

aircraft — Aero.FixedWing object

scalar

`Aero.FixedWing` object, returned as a scalar. The method defines the aircraft coefficients of the object as `Simulink.LookupTable` objects derived from the coefficient fields in the Digital DATCOM structure `datcomStruct`.

state — Array of Aero.FixedWing.State objects

array

`Aero.FixedWing.State` objects, returned as an array. The value depends on the `StateMode` value.

Examples

Construct Fixed-Wing Aircraft from Digital DATCOM File

Construct a fixed-wing aircraft from an imported Digital DATCOM file.

```
datcomStruct = datcomimport('astdatcom.out');
aircraft = Aero.FixedWing();
aircraft.Properties.Name = "MyPlane";
aircraft = datcomToFixedWing(aircraft, datcomStruct{1})
```

```
aircraft =
```

```
FixedWing with properties:
```

```

ReferenceArea: 225.8000
ReferenceSpan: 41.1500
ReferenceLength: 5.7500
Coefficients: [1x1 Aero.FixedWing.Coefficient]
DegreesOfFreedom: "6DOF"
Surfaces: [1x0 Aero.FixedWing.Surface]
Thrusts: [1x0 Aero.FixedWing.Thrust]
AspectRatio: 7.4992
UnitSystem: "English (ft/s)"
AngleSystem: "Degrees"
TemperatureSystem: "Rankine"
Properties: [1x1 Aero.Aircraft.Properties]

```

Construct Fixed-Wing Aircraft from Digital DATCOM File with Build Number

Construct fixed-wing aircraft from Digital DATCOM file, specifying the build number.

```

datcomStruct = datcomimport('astdatcom.out');
aircraft = Aero.FixedWing();
aircraft.Properties.Name = "MyPlane";
aircraft = datcomToFixedWing(aircraft,datcomStruct{1},'Build',1)

```

```
aircraft =
```

FixedWing with properties:

```

ReferenceArea: 225.8000
ReferenceSpan: 41.1500
ReferenceLength: 5.7500
Coefficients: [1x1 Aero.FixedWing.Coefficient]
DegreesOfFreedom: "6DOF"
Surfaces: [1x0 Aero.FixedWing.Surface]
Thrusts: [1x0 Aero.FixedWing.Thrust]
AspectRatio: 7.4992
UnitSystem: "English (ft/s)"
AngleSystem: "Degrees"
TemperatureSystem: "Rankine"
Properties: [1x1 Aero.Aircraft.Properties]

```

Construct Fixed-Wing Aircraft from Digital DATCOM File with 'Exhaustive' StateMode

Construct a fixed-wing aircraft from an imported Digital DATCOM file and return the exhaustive state array.

```

datcomStruct = datcomimport('astdatcom.out');
aircraft = Aero.FixedWing();
aircraft.Properties.Name = "MyPlane";
[aircraft,state] = datcomToFixedWing(aircraft,datcomStruct{1},'StateMode','Exhaustive')

```

```
aircraft =
```

FixedWing with properties:

```

ReferenceArea: 225.8000
ReferenceSpan: 41.1500
ReferenceLength: 5.7500
Coefficients: [1x1 Aero.FixedWing.Coefficient]

```

```
DegreesOfFreedom: "6DOF"  
  Surfaces: [1x0 Aero.FixedWing.Surface]  
  Thrusts: [1x0 Aero.FixedWing.Thrust]  
  AspectRatio: 7.4992  
  UnitSystem: "English (ft/s)"  
  AngleSystem: "Degrees"  
  TemperatureSystem: "Rankine"  
  Properties: [1x1 Aero.Aircraft.Properties]
```

state =

5x2x2 State array with properties:

```
Alpha  
Beta  
AlphaDot  
BetaDot  
Mass  
Inertia  
CenterOfGravity  
CenterOfPressure  
AltitudeMSL  
GroundHeight  
XN  
XE  
XD  
U  
V  
W  
Phi  
Theta  
Psi  
P  
Q  
R  
Weight  
AltitudeAGL  
Airspeed  
GroundSpeed  
MachNumber  
BodyVelocity  
GroundVelocity  
Ur  
Vr  
Wr  
FlightPathAngle  
CourseAngle  
InertialToBodyMatrix  
BodyToInertialMatrix  
BodyToWindMatrix  
WindToBodyMatrix  
DynamicPressure  
Environment  
UnitSystem  
AngleSystem  
TemperatureSystem  
ControlStates
```

OutOfRangeAction
DiagnosticAction
Properties

Limitations

- This method supports only Digital DATCOM, which is the 1976 version of DATCOM.
- This fields `alpha`, `mach`, `alt`, `grndht`, and `delta` must be strictly monotonically increasing.
- This method requires a Simulink license.

See Also

`Aero.FixedWing` | `Simulink.LookupTable` | `datcomimport`

Introduced in R2021a

dcm2alphabeta

Convert direction cosine matrix to angle of attack and sideslip angle

Syntax

```
[alpha beta] = dcm2alphabeta(dcm)
[alpha beta] = dcm2alphabeta(dcm,action)
[alpha beta] = dcm2alphabeta( ____,tolerance)
```

Description

`[alpha beta] = dcm2alphabeta(dcm)` calculates the angle of attack (`alpha`) and sideslip angle (`beta`) for the direction cosine matrix, `dcm`. The function transforms the coordinates from a vector in body axes into a vector in wind axes.

`[alpha beta] = dcm2alphabeta(dcm,action)` performs `action` if the `dcm` is not orthogonal.

`[alpha beta] = dcm2alphabeta(____,tolerance)` uses a `tolerance` level to evaluate if the direction cosine matrix, `dcm`, is orthogonal. Specify `tolerance` after all other input arguments.

Examples

Determine Angle of Attack and Sideslip Angle from Direction Cosine Matrix

Determine the angle of attack and sideslip angle from a direction cosine matrix:

```
dcm = [ 0.8926    0.1736    0.4162; ...
        -0.1574    0.9848   -0.0734; ...
        -0.4226     0        0.9063];
[alpha, beta] = dcm2alphabeta(dcm)
```

```
alpha =
    0.4363
```

```
beta =
    0.1745
```

Determine Angle of Attack and Sideslip Angle from Multiple Direction Cosine Matrices

Determine the angle of attack and sideslip angle from multiple direction cosine matrices:

```
dcm = [ 0.8926    0.1736    0.4162; ...
        -0.1574    0.9848   -0.0734; ...
        -0.4226     0        0.9063];
dcm(:, :, 2) = [ 0.9811    0.0872    0.1730; ...
                -0.0859    0.9962   -0.0151; ...
```

```

        -0.1736      0      0.9848];
[alpha, beta] = dcm2alphabeta(dcm)

alpha =

    0.4363
    0.1745

beta =

    0.1745
    0.0873

```

Determine Angle of Attack and Sideslip Angle from Multiple Direction Cosine Matrices within Tolerance

Determine the angle of attack and sideslip angle from multiple direction cosine matrices. Return a warning if the dcm exceeds a tolerance of 0.1:

```

dcm = [ 0.8926      0.1736      0.4162; ...
       -0.1574      0.9848     -0.0734; ...
       -0.4226         0         0.9063];
dcm(:,:,2) = [ 0.9811      0.0872      0.1730; ...
              -0.0859      0.9962     -0.0151; ...
              -0.1736         0         0.9848];
[alpha, beta] = dcm2alphabeta(dcm, 'Warning', 0.1)

alpha =

    0.4363
    0.1745

beta =

    0.1745
    0.0873

```

Input Arguments

dcm — Direction cosine matrices

3-by-3-by-*m* matrix

Direction cosine matrices, specified as a 3-by-3-by-*m* matrix, where *m* is the number of direction cosine matrices. dcm contains *m* orthogonal direction cosine matrices.

action — Action

'None' (default) | 'Error' | 'Warning'

Action for invalid direction cosine matrices, specified as:

- 'Warning' — Displays warning and indicates that the direction cosine matrix is invalid.
- 'Error' — Displays error and indicates that the direction cosine matrix is invalid.
- 'None' — Does not display warning or error.

Data Types: char | string

tolerance — Relative tolerance

eps(2) (default) | scalar

Tolerance level to evaluate if the direction cosine matrix, `dcm`, is orthogonal, specified as a scalar.

The function considers the direction cosine matrix valid if these conditions are true:

- The transpose of the direction cosine matrix times itself equals 1 within the specified tolerance ($\text{transpose}(n)*n == 1 \pm \text{tolerance}$)
- The determinant of the direction cosine matrix equals 1 within the specified tolerance ($\text{det}(n) == 1 \pm \text{tolerance}$).

Data Types: double

Output Arguments**alpha — Angles of attack**

array

Angles of attack, returned as an array of m angles of attack, in radians.

beta — Sideslip angles

array

Sideslip angles, returned as an m array of sideslip angles, in radians.

See Also

angle2dcm | dcm2angle | dcmbody2wind

Introduced in R2006b

dcm2angle

Create rotation angles from direction cosine matrix

Syntax

```
[rotationAng1 rotationAng2 rotationAng3] = dcm2angle(dcm)
[rotationAng1 rotationAng2 rotationAng3] = dcm2angle(dcm,rotationSequence)
[rotationAng1 rotationAng2 rotationAng3] = dcm2angle( ____,lim)
[rotationAng1 rotationAng2 rotationAng3] = dcm2angle( ____,action)
[rotationAng1 rotationAng2 rotationAng3] = dcm2angle( ____,tolerance)
```

Description

[rotationAng1 rotationAng2 rotationAng3] = dcm2angle(dcm) calculates the rotation angles, rotationAng1, rotationAng2, rotationAng3, for a direction cosine matrix, dcm. This function uses a passive transformation between two coordinate systems.

[rotationAng1 rotationAng2 rotationAng3] = dcm2angle(dcm,rotationSequence) calculates the rotation angles for a specified rotation sequence, rotationSequence.

[rotationAng1 rotationAng2 rotationAng3] = dcm2angle(____,lim) calculates the rotation angles for a specified angle constraint, lim. Specify lim after all other input arguments.

[rotationAng1 rotationAng2 rotationAng3] = dcm2angle(____,action) calculates the rotation angles and performs an action if the direction cosine matrix is not orthogonal. Specify action after all other input arguments.

[rotationAng1 rotationAng2 rotationAng3] = dcm2angle(____,tolerance) calculates the rotation angles and uses a tolerance level to evaluate if the direction cosine matrix is orthogonal. Specify tolerance after all other input arguments.

Examples

Determine Rotation Angles from Direction Cosine Matrix

Determine the rotation angles from the direction cosine matrix:

```
dcm = [1 0 0; 0 1 0; 0 0 1];
[yaw, pitch, roll] = dcm2angle(dcm)
```

```
yaw =
    0
```

```
pitch =
    0
```

```
roll =
    0
```

Determine Rotation Angles from Multiple Direction Cosine Matrices

Determine the rotation angles from multiple direction cosine matrices:

```
dcm      = [ 1 0 0; 0 1 0; 0 0 1];
dcm(:,:,2) = [ 0.85253103550038    0.47703040785184   -0.21361840626067; ...
              -0.43212157513194    0.87319830445628    0.22537893734811; ...
              0.29404383655186   -0.09983341664683    0.95056378592206];
[pitch, roll, yaw] = dcm2angle(dcm, 'YZX', 'Default', 'None', 0.1)

pitch =
     0
    0.3000

roll =
     0
    0.1000

yaw =
     0
    0.5000
```

Input Arguments

dcm — Direction cosine matrices

3-by-3-by-*m* matrix

Direction cosine matrices, specified as a 3-by-3-by-*m* matrix, where *m* is the number of direction cosine matrices. The direction cosine matrices must be orthogonal with determinant +1.

rotationSequence — Rotation sequence

'ZYX' (default) | 'ZYX' | 'ZYZ' | 'ZXY' | 'ZXZ' | 'YXZ' | 'YXY' | 'YZX' | 'YZY' | 'XYZ' | 'XZY' | 'YXX' | 'XZX'

Rotation sequence, specified as:

- 'ZYX'
- 'ZYZ'
- 'ZXY'
- 'ZXZ'
- 'YXZ'
- 'YXY'
- 'YZX'
- 'YZY'
- 'XYZ'
- 'XZY'
- 'YXX'
- 'XZX'

where rotationAng1 is the z-axis rotation, rotationAng2 is the y-axis rotation, and rotationAng3 is the x-axis rotation.

Data Types: char | string

Lim — Angle constraint

'Default' (default) | 'ZeroR3'

Angle constraint, specified as 'Default' or 'ZeroR3'. For more information on angle constraints, see “Limitations” on page 4-269.

action — Action for invalid direction cosine matrix

'None' (default) | 'Error' | 'Warning'

Action for invalid direction cosine matrix, specified as:

- 'Warning' — Displays warning and indicates that the direction cosine matrix is invalid.
- 'Error' — Displays error and indicates that the direction cosine matrix is invalid.
- 'None' — Does not display warning or error.

Data Types: char | string

tolerance — Relative tolerance

eps(2) (default) | scalar

Tolerance level to evaluate if the direction cosine matrix, dcm, is orthogonal, specified as a scalar.

The function considers the direction cosine matrix valid if these conditions are true:

- The transpose of the direction cosine matrix times itself equals 1 within the specified tolerance $\text{tolerance}(\text{transpose}(\text{dcm}) * \text{dcm} == 1 \pm \text{tolerance})$
- The determinant of the direction cosine matrix equals 1 within the specified tolerance $(\text{det}(\text{dcm}) == 1 \pm \text{tolerance})$.

Data Types: char | string

Output Arguments

rotationAng1 — First rotation angles

m-by-1 array

First rotation angles, returned as an *m*-by-1 array, in rads.

rotationAng2 — Second rotation angles

m-by-1 array

Second rotation angles, returned as an *m*-by-1 array, in rads.

rotationAng3 — Third rotation angles

m-by-1 array

Third rotation angles, returned as an *m*-by-1 array, in rads.

Limitations

- The 'Default' limitations for the 'ZYX', 'ZXY', 'YXZ', 'YZX', 'XYZ', and 'XZY' implementations generate a `rotationAng2` angle that lies between ± 90 degrees, and `rotationAng1` and `rotationAng3` angles that lie between ± 180 degrees.
- The 'Default' limitations for the 'YZY', 'ZXZ', 'YXY', 'ZYX', 'XYX', and 'XZX' implementations generate a `rotationAng2` angle that lies between 0-180 degrees, and `rotationAng1` and `rotationAng3` angles that lie between ± 180 degrees.
- The 'ZeroR3' limitations for the 'ZYX', 'ZXY', 'YXZ', 'YZX', 'XYZ', and 'XZY' implementations generate a `rotationAng2` angle that lies between ± 90 degrees, and `rotationAng1` and `rotationAng3` angles that lie between ± 180 degrees. However, when `rotationAng2` is ± 90 degrees, `rotationAng3` is set to 0 degrees.
- The 'ZeroR3' limitations for the 'YZY', 'ZXZ', 'YXY', 'ZYX', 'XYX', and 'XZX' implementations generate a `rotationAng2` angle that lies between 0-180 degrees, and `rotationAng1` and `rotationAng3` angles that lie between ± 180 degrees. However, when `rotationAng2` is 0 or ± 180 degrees, `rotationAng3` is set to 0 degrees.

See Also

`angle2dcm` | `dcm2quat` | `quat2angle` | `quat2dcm`

Introduced in R2006b

dcm2latlon

Convert direction cosine matrix to geodetic latitude and longitude

Syntax

```
[lat lon] = dcm2latlon(n)
[lat lon] = dcm2latlon(n,action)
[lat lon] = dcm2latlon(n,action,tolerance)
```

Description

`[lat lon] = dcm2latlon(n)` calculates the geodetic latitude and longitude, `lat` and `lon`, for a given direction cosine matrix, `n`. `n` is a 3-by-3-by-`m` matrix containing `m` orthogonal direction cosine matrices. `lat` is an `m` array of geodetic latitudes. `lon` is an `m` array of longitudes. `n` performs the coordinate transformation of a vector in Earth-centered Earth-fixed (ECEF) axes into a vector in north-east-down (NED) axes. Geodetic latitudes and longitudes are output in degrees.

`[lat lon] = dcm2latlon(n,action)` performs `action` if the direction cosine matrix is invalid (not orthogonal).

- Warning — Displays warning and indicates that the direction cosine matrix is invalid.
- Error — Displays error and indicates that the direction cosine matrix is invalid.
- None — Does not display warning or error (default).

`[lat lon] = dcm2latlon(n,action,tolerance)` uses a `tolerance` level to evaluate if the direction cosine matrix, `n`, is valid (orthogonal). `tolerance` is a scalar whose default is `eps(2)` ($4.4409e-16$). The function considers the direction cosine matrix valid if these conditions are true:

- The transpose of the direction cosine matrix times itself equals 1 within the specified tolerance (`transpose(n)*n == 1±tolerance`)
- The determinant of the direction cosine matrix equals 1 within the specified tolerance (`det(n) == 1±tolerance`).

Examples

Determine the geodetic latitude and longitude from direction cosine matrix:

```
dcm = [ 0.3747    0.5997    0.7071; ...
        0.8480   -0.5299         0; ...
        0.3747    0.5997   -0.7071];
[lat, lon] = dcm2latlon(dcm)
```

```
lat =
```

```
    44.9995
```

```
lon =
```

```
 -122.0005
```

Determine the geodetic latitude and longitude from multiple direction cosine matrices:

```
dcm = [ 0.3747    0.5997    0.7071; ...
        0.8480   -0.5299         0; ...
        0.3747    0.5997   -0.7071];
dcm(:,:,2) = [-0.0531    0.6064    0.7934; ...
              0.9962    0.0872         0; ...
              -0.0691    0.7903   -0.6088];
[lat, lon] = dcm2latlon(dcm)
```

```
lat =
    44.9995
    37.5028
```

```
lon =
   -122.0005
    -84.9975
```

Determine the geodetic latitude and longitude from multiple direction cosine matrices validated within tolerance:

```
dcm = [ 0.3747    0.5997    0.7071; ...
        0.8480   -0.5299         0; ...
        0.3747    0.5997   -0.7071];
dcm(:,:,2) = [-0.0531    0.6064    0.7934; ...
              0.9962    0.0872         0; ...
              -0.0691    0.7903   -0.6088];
[lat, lon] = dcm2latlon(dcm,'Warning',0.1)
```

```
lat =
    44.9995
    37.5028
lon =
   -122.0005
    -84.9975
```

See Also

[angle2dcm](#) | [dcm2angle](#) | [dcmecef2ned](#)

Introduced in R2006b

dcm2quat

Convert direction cosine matrix to quaternion

Syntax

```
q = dcm2quat(n)
q = dcm2quat(n,action)
q = dcm2quat(n,action,tolerance)
```

Description

`q = dcm2quat(n)` calculates the quaternion, `q`, for a given direction cosine matrix, `n`. Input `n` is a 3-by-3-by-`m` matrix of orthogonal direction cosine matrices. The direction cosine matrix performs the coordinate transformation of a vector in inertial axes to a vector in body axes. `q` returns an `m`-by-4 matrix containing `m` quaternions. `q` has its scalar number as the first column.

This function applies only to direction cosine matrices that are orthogonal with determinant +1.

`q = dcm2quat(n,action)` performs `action` if the direction cosine matrix is invalid (not orthogonal).

- Warning — Displays warning and indicates that the direction cosine matrix is invalid.
- Error — Displays error and indicates that the direction cosine matrix is invalid.
- None — Does not display warning or error (default).

`q = dcm2quat(n,action,tolerance)` uses a `tolerance` level to evaluate if the direction cosine matrix, `n`, is valid (orthogonal). `tolerance` is a scalar whose default is `eps(2)` ($4.4409e-16$). The function considers the direction cosine matrix valid if these conditions are true:

- The transpose of the direction cosine matrix times itself equals 1 within the specified tolerance (`transpose(n)*n == 1±tolerance`)
- The determinant of the direction cosine matrix equals 1 within the specified tolerance (`det(n) == 1±tolerance`).

Examples

Determine the quaternion from direction cosine matrix:

```
dcm = [0 1 0; 1 0 0; 0 0 -1];
q = dcm2quat(dcm)
q =
```

```
0    0.7071    0.7071    0
```

Determine the quaternions from multiple direction cosine matrices:

```
dcm          = [ 0 1 0; 1 0 0; 0 0 -1];
dcm(:,:,2) = [ 0.4330    0.2500   -0.8660; ...
               0.1768    0.9186    0.3536; ...
               0.8839   -0.3062    0.3536];
```



```
q = dcm2quat(dcm)
q =
```

```
    0    0.7071    0.7071    0
0.8224    0.2006    0.5320    0.0223
```

Determine the quaternion from a direction cosine matrix validated within tolerance:

```
dcm = [0 1 0; 1 0 0; 0 0 -1];
q = dcm2quat(dcm, 'Warning', 0.1)
```

```
q =
```

```
    0    0.7071    0.7071    0
```

See Also

[angle2dcm](#) | [angle2quat](#) | [dcm2angle](#) | [quat2angle](#) | [quat2dcm](#)

Introduced in R2006b

dcm2rod

Convert direction cosine matrix to Euler-Rodrigues vector

Syntax

```
R = dcm2rod(dcm)
R = dcm2rod(dcm,action)
R = dcm2rod(dcm,action,tolerance)
```

Description

`R = dcm2rod(dcm)` function calculates the Euler-Rodrigues vector (**R**) from the direction cosine matrix. This function applies only to direction cosine matrices that are orthogonal with determinant +1.

`R = dcm2rod(dcm,action)` performs **action** if the direction cosine matrix is invalid (not orthogonal).

`R = dcm2rod(dcm,action,tolerance)` uses a tolerance level to evaluate if the direction cosine matrix, **n**, is valid (orthogonal).

Examples

Determine Rodrigues Vector from Direction Cosine Matrix

Determine the Rodrigues vector from the direction cosine matrix.

```
DCM = [0.433 0.75 0.5;-0.25 -0.433 0.866;0.866 -0.5 0.0];
r = dcm2rod(DCM)
```

```
r =
    1.3660    0.3660    1.0000
```

Determine Rodrigues Vector from Direction Cosine Matrix Validated within Tolerance:

Determine the Rodrigues vector from the direction cosine matrix validated within tolerance.

```
DCM = [0.433 0.75 0.5;-0.25 -0.433 0.866;0.866 -0.5 0.0];
r = dcm2rod(DCM, 'Warning',0.1)
```

```
r =
    1.3660    0.3660    1.0000
```

Input Arguments

dcm — Direction cosine matrix
3-by-3-by-*M* matrix

3-by-3-by- M containing M direction cosine matrices.

Data Types: double

action — Function behavior

'None' (default) | 'Error' | 'Warning'

Function behavior when direction cosine matrix is invalid (not orthogonal).

- Warning — Displays warning and indicates that the direction cosine matrix is invalid.
- Error — Displays error and indicates that the direction cosine matrix is invalid.
- None — Does not display warning or error (default).

Data Types: char | string

tolerance — Tolerance

eps(2) (4.4409e-16) (default) | scalar

Tolerance of direction cosine matrix validity, specified as a scalar. The function considers the direction cosine matrix valid if these conditions are true:

- The transpose of the direction cosine matrix times itself equals 1 within the specified tolerance ($\text{transpose}(n)*n == 1 \pm \text{tolerance}$)
- The determinant of the direction cosine matrix equals 1 within the specified tolerance ($\det(n) == 1 \pm \text{tolerance}$).

Data Types: double

Output Arguments

R — Rodrigues vector

M -by-3 matrix

M -by-3 matrix containing M Rodrigues vectors.

Data Types: double

Algorithms

An Euler-Rodrigues vector \vec{b} represents a rotation by integrating a direction cosine of a rotation axis with the tangent of half the rotation angle as follows:

$$\vec{b} = [b_x \ b_y \ b_z]$$

where:

$$b_x = \tan\left(\frac{1}{2}\theta\right)s_x,$$

$$b_y = \tan\left(\frac{1}{2}\theta\right)s_y,$$

$$b_z = \tan\left(\frac{1}{2}\theta\right)s_z$$

are the Rodrigues parameters. Vector \vec{s} represents a unit vector around which the rotation is performed. Due to the tangent, the rotation vector is indeterminate when the rotation angle equals $\pm\pi$ radians or ± 180 deg. Values can be negative or positive.

References

- [1] Dai, J.S. "Euler-Rodrigues formula variations, quaternion conjugation and intrinsic connections." *Mechanism and Machine Theory*, 92, 144-152. Elsevier, 2015.

See Also

[angle2rod](#) | [quat2rod](#) | [rod2angle](#) | [rod2dcm](#) | [rod2quat](#)

Introduced in R2017a

dcmbody2wind

Convert angle of attack and sideslip angle to direction cosine matrix

Syntax

```
n = dcmbody2wind(a, b)
```

Description

`n = dcmbody2wind(a, b)` calculates the direction cosine matrix, `n`, for given angle of attack and sideslip angle, `a`, `b`. `a` is an `m` array of angles of attack. `b` is an `m` array of sideslip angles. `n` returns a 3-by-3-by-`m` matrix containing `m` direction cosine matrices. `n` performs the coordinate transformation of a vector in body-axes into a vector in wind-axes. Angles of attack and sideslip angles are input in radians.

Examples

Determine the direction cosine matrix from angle of attack and sideslip angle:

```
alpha = 0.4363;
beta = 0.1745;
dcm = dcmbody2wind(alpha, beta)
```

dcm =

```
    0.8926    0.1736    0.4162
   -0.1574    0.9848   -0.0734
   -0.4226         0    0.9063
```

Determine the direction cosine matrix from multiple angles of attack and sideslip angles:

```
alpha = [0.4363 0.1745];
beta = [0.1745 0.0873];
dcm = dcmbody2wind(alpha, beta)
```

dcm(:,:,1) =

```
    0.8926    0.1736    0.4162
   -0.1574    0.9848   -0.0734
   -0.4226         0    0.9063
```

dcm(:,:,2) =

```
    0.9811    0.0872    0.1730
   -0.0859    0.9962   -0.0151
   -0.1736         0    0.9848
```

See Also

[angle2dcm](#) | [dcm2alphabeta](#) | [dcm2angle](#)

Introduced in R2006b

dcmecef2ned

Convert geodetic latitude and longitude to direction cosine matrix

Syntax

```
n = dcmecef2ned(lat, lon)
```

Description

`n = dcmecef2ned(lat, lon)` calculates the direction cosine matrix, `n`, for a given set of geodetic latitude and longitude, `lat`, `lon`. `lat` is an `m` array of geodetic latitudes. `lon` is an `m` array of longitudes. Latitude and longitude values can be any value. However, latitude values of +90 and -90 may return unexpected values because of singularity at the poles. `n` returns a 3-by-3-by-`m` matrix containing `m` direction cosine matrices. `n` performs the coordinate transformation of a vector in Earth-centered Earth-fixed (ECEF) axes into a vector in north-east-down (NED) axes. Geodetic latitudes and longitudes are input in degrees.

Examples

Determine the direction cosine matrix from geodetic latitude and longitude:

```
lat = 45;
lon = -122;
dcm = dcmecef2ned(lat, lon)

dcm =

    0.3747    0.5997    0.7071
    0.8480   -0.5299         0
    0.3747    0.5997   -0.7071
```

Determine the direction cosine matrix from multiple geodetic latitudes and longitudes:

```
lat = [45 37.5];
lon = [-122 -85];
dcm = dcmecef2ned(lat, lon)

dcm(:, :, 1) =

    0.3747    0.5997    0.7071
    0.8480   -0.5299         0
    0.3747    0.5997   -0.7071

dcm(:, :, 2) =

   -0.0531    0.6064    0.7934
    0.9962    0.0872         0
   -0.0691    0.7903   -0.6088
```

See Also

`angle2dcm` | `dcm2angle` | `dcm2latlon`

Introduced in R2006b

dcmeci2ecef

Convert Earth-centered inertial (ECI) to Earth-centered Earth-fixed (ECEF) coordinates

Syntax

```
dcm=dcmeci2ecef(reduction,utc)

dcm=dcmeci2ecef(reduction,utc,deltaAT)
dcm=dcmeci2ecef(reduction,utc,deltaAT,deltaUT1)
dcm=dcmeci2ecef(reduction,utc,deltaAT,deltaUT1,polarmotion)
dcm=dcmeci2ecef(reduction,utc,deltaAT,deltaUT1,polarmotion,Name,Value)
```

Description

`dcm=dcmeci2ecef(reduction,utc)` calculates the position direction cosine matrix (ECI to ECEF) as a 3-by-3-by-*M* array. The calculation is based on the specified reduction method and Universal Coordinated Time (UTC).

`dcm=dcmeci2ecef(reduction,utc,deltaAT)` uses the difference between International Atomic Time and UTC to calculate the position direction cosine matrix.

`dcm=dcmeci2ecef(reduction,utc,deltaAT,deltaUT1)` uses the difference between UTC and Universal Time (UT1).

`dcm=dcmeci2ecef(reduction,utc,deltaAT,deltaUT1,polarmotion)` uses the polar displacement.

`dcm=dcmeci2ecef(reduction,utc,deltaAT,deltaUT1,polarmotion,Name,Value)` uses additional options specified by one or more Name,Value pair arguments.

Examples

Convert using IAU-2000/2006 reduction

Convert Earth-centered inertial (ECI) to Earth-centered Earth-fixed (ECEF) coordinates for January 12, 2000 at 4 hours, 52 minutes, 12.4 seconds and January 12, 2000 at 4 hours, 52 minutes, and 13 seconds. Use the IAU-2000/2006 reduction. Specify only the reduction method and UTC.

```
dcm = dcmeci2ecef('IAU-2000/2006',[2000 1 12 4 52 12.4;2000 1 12 4 52 13])
```

```
dcm(:, :, 1) =
```

```
   -0.9975   -0.0708   -0.0000
    0.0708   -0.9975   -0.0000
   -0.0000   -0.0000    1.0000
```

```
dcm(:, :, 2) =
```

```
   -0.9975   -0.0709   -0.0000
```

```

0.0709   -0.9975   -0.0000
-0.0000   -0.0000   1.0000

```

Convert using IAU-76/FK5 reduction

Convert Earth-centered inertial (ECI) to Earth-centered Earth-fixed (ECEF) coordinates for January 12, 2000 at 4 hours, 52 minutes, 12.4 seconds. Use the IAU-76/FK5 reduction. Specify all arguments, including optional ones such as polar motion.

```

dcm = dcmeci2ecef('IAU-76/FK5',[2000 1 12 4 52 12.4],32,0.234,[-0.0682e-5 ...
0.1616e-5], 'dNutation',[-0.2530e-6 -0.0188e-6])

```

dcm =

```

-0.9975   -0.0708   -0.0000
 0.0708   -0.9975   -0.0000
-0.0000   -0.0000   1.0000

```

Input Arguments

reduction — Reduction method

'IAU-76/FK5' | 'IAU-2000/2006'

Reduction method to calculate the direction cosine matrix, specified as one of the following:

- IAU-76/FK5

Reduce the calculation using the International Astronomical Union (IAU)-76/Fifth Fundamental Catalogue (FK5) (IAU-76/FK5) reference system. Choose this reduction method if the reference coordinate system for the conversion is FK5. You can use the 'dNutation' Name,Value pair with this reduction.

Note This method uses the IAU 1976 precession model and the IAU 1980 theory of nutation to reduce the calculation. This model and theory are no longer current, but the software provides this reduction method for existing implementations. Because of the polar motion approximation that this reduction method uses, `dcmeci2ecef` calculates the transformation matrix rather than the direction cosine matrix.

- IAU-2000/2006

Reduce the calculation using the International Astronomical Union (IAU)-2000/2005 reference system. Choose this reduction method if the reference coordinate system for the conversion is IAU-2000. This reduction method uses the P03 precession model to reduce the calculation. You can use the 'dCIP' Name,Value pair with this reduction.

utc — Universal Coordinated Time

1-by-6 array | *M*-by-6 matrix

Universal Coordinated Time (UTC) in the order year, month, day, hour, minutes, and seconds, for which the function calculates the direction cosine matrix, specified as one of the following.

- For the year value, enter a double value that is a whole number greater than 1, such as 2013.
- For the month value, enter a double value that is a whole number greater than 0, within the range 1 to 12.

- For the day value, enter a double value that is a whole number greater than 0, within the range 1 to 31.
- For the hour value, enter a double value that is a whole number greater than 0, within the range 1 to 24.
- For the minute and second values, enter a double value that is a whole number greater than 0, within the range 1 to 60.

Specify these values in one of the following formats:

- 1-by-6 array

Specify a 1-row-by-6-column array of UTC values to calculate one direction cosine or transformation matrix.

- M -by-6 matrix

Specify an M -by-6 array of UTC values, where M is the number of direction cosine or transformation matrices to calculate. Each row corresponds to one set of UTC values.

Example: [2000 1 12 4 52 12.4]

This is a one row-by-6 column array of UTC values.

Example: [2000 1 12 4 52 12.4;2010 6 5 7 22 0]

This is an M -by-6 array of UTC values, where M is 2.

Data Types: double

deltaAT — Difference between International Atomic Time and UTC

scalar | one-dimensional array

Difference between International Atomic Time (IAT) and UTC, in seconds, for which the function calculates the direction cosine or transformation matrix. By default, the function assumes an M -by-1 array of zeroes.

- scalar

Specify one difference-time value to calculate one direction cosine or transformation matrix.

- one-dimensional array

Specify a one-dimensional array with M elements, where M is the number of direction cosine or transformation matrices to calculate. Each row corresponds to one set of UTC values.

Example: 32

Specify 32 seconds as the difference between IAT and UTC.

Data Types: double

deltaUT1 — Difference between UTC and Universal Time (UT1)

scalar | one-dimensional array

Difference between UTC and Universal Time (UT1) in seconds, for which the function calculates the direction cosine or transformation matrix. By default, the function assumes an M -by-1 array of zeroes.

- scalar

Specify one difference-time value to calculate one direction cosine or transformation matrix.

- one-dimensional array

Specify a one-dimensional array with M elements of difference time values, where M is the number of direction cosine or transformation matrices to be calculated. Each row corresponds to one set of UTC values.

Example: `0.234`

Specify `0.234` seconds as the difference between UTC and UT1.

Data Types: `double`

polarmotion — Polar displacement

1-by-2 array | M -by-2 array

Polar displacement of the Earth, in radians, from the motion of the Earth crust, along the x - and y -axes. By default, the function assumes an M -by-2 array of zeroes.

- 1-by-2 array

Specify a 1-by-2 array of the polar displacement values to convert one direction cosine or transformation matrix.

- M -by-2 array

Specify an M -by-2 array of polar displacement values, where M is the number of direction cosine or transformation matrices to convert. Each row corresponds to one set of UTC values.

Example: `[-0.0682e-5 0.1616e-5]`

Data Types: `double`

Name-Value Pair Arguments

Specify optional comma-separated pairs of `Name`, `Value` arguments. `Name` is the argument name and `Value` is the corresponding value. `Name` must appear inside quotes. You can specify several name and value pair arguments in any order as `Name1, Value1, . . . , NameN, ValueN`.

Example: `[-0.2530e-6 -0.0188e-6]`

dNutation — Adjustment to longitude (*dDeltaPsi*) and obliquity (*dDeltaEpsilon*)

M -by-2 array

Adjustment to the longitude (*dDeltaPsi*) and obliquity (*dDeltaEpsilon*), in radians, as the comma-separated pair consisting of `dNutation` and an M -by-2 array. Use this `Name, Value` pair with the IAU-76/FK5 reduction. By default, the function assumes an M -by-2 array of zeroes.

For historical values, see the International Earth Rotation and Reference Systems Service Web site (<https://www.iers.org>) and navigate to the Earth Orientation Data Data/Products page.

- M -by-2 array

Specify M -by-2 array of adjustment values, where M is the number of direction cosine or transformation matrices to be converted. Each row corresponds to one set of longitude and obliquity values.

Data Types: double

dCIP — Adjustment to the location of the Celestial Intermediate Pole (CIP)

M-by-2 array

Adjustment to the location of the Celestial Intermediate Pole (CIP), in radians, specified as the comma-separated pair consisting of dCIP and an *M*-by-2 array. This location (*dDeltaX*, *dDeltaY*) is along the *x*- and *y*- axes. Use this argument with the IAU-200/2006 reduction. By default, this function assumes an *M*-by-2 array of zeroes.

For historical values, see the International Earth Rotation and Reference Systems Service Web site (<https://www.iers.org>) and navigate to the Earth Orientation Data Data/Products page.

- *M*-by-2 array

Specify *M*-by-2 array of location adjustment values, where *M* is the number of direction cosine or transformation matrices to be converted. Each row corresponds to one set of *dDeltaX* and *dDeltaY* values.

Example: [-0.2530e-6 -0.0188e-6]

Data Types: double

Output Arguments

dcm — Direction cosine or transformation matrix

3-by-3-*M* array

Direction cosine or transformation matrix, returned as a 3-by-3-*M* array.

See Also

[ecef2lla](#) | [geoc2geod](#) | [geod2geoc](#) | [lla2ecef](#)

Topics

<https://www.iers.org>

Introduced in R2013b

decyear

Decimal year calculator

Syntax

```
dy = decyear(dateVector)
dy = decyear(dateCharacterVector, format)
dy = decyear(year, month, day)
dy = decyear([year, month, day])
dy = decyear(year, month, day, hour, minute, second)
dy = decyear([year, month, day, hour, minute, second])
```

Description

`dy = decyear(dateVector)` converts one or more date vectors, `dateVector`, into decimal year, `dy`.

`dy = decyear(dateCharacterVector, format)` converts one or more date character vectors, `dateCharacterVector`, to decimal year using format `format`.

`dy = decyear(year, month, day)` and `dy = decyear([year, month, day])` return the decimal year for corresponding elements of the `year`, `month`, `day` arrays.

`dy = decyear(year, month, day, hour, minute, second)` and `dy = decyear([year, month, day, hour, minute, second])` return the decimal year for corresponding elements of the `year`, `month`, `day`, `hour`, `minute`, `second` arrays. Specify the six arguments as one-dimensional arrays of the same length or as scalar values.

Examples

Calculate Decimal Year Using Data Character Vector and dd-mm-yyyy Format

Calculate decimal year for May 24, 2005 using data character vector and dd-mm-yyyy format:

```
dy = decyear('24-May-2005', 'dd-mmm-yyyy')
dy =
  2.0054e+03
```

Calculate Decimal Year Using Year, Month, and Day Inputs

Calculate the decimal year for December 19, 2006 from year, month, and day inputs:

```
dy = decyear(2006, 12, 19)
dy =
  2.0070e+03
```

Calculate Decimal Year from Year, Month, Day, Hour, Minute, and Second Inputs

Calculate the decimal year for October 10, 2004, at 12:21:00 p.m. from year, month, day, hour, month, and second inputs:

```
dy = decyear(2004,10,10,12,21,0)
```

```
dy =  
    2.0048e+003
```

Input Arguments

dateVector — Full or partial date vector

m-by-6 matrix | *m*-by-3 matrix | positive double-precision number

Full or partial date vector, specified as an *m*-by-6 or *m*-by-3 matrix containing *m* full or partial date vectors, respectively:

- Full date vector — Contains six elements specifying the year, month, day, hour, minute, and second
- Partial date vector — Contains three elements specifying the year, month, and day

Data Types: `double`

dateCharacterVector — Date character vector

character array | one-dimensional cell array of character vectors

Date character vector, specified as a character array, where each row corresponds to one date, or a one-dimensional cell array of character vectors.

Data Types: `char` | `string`

format — Date format

-1 (default) | character vector | string scalar | integer

Date format, specified as a character vector, string scalar, or integer. All dates in `dateCharacterVector` must have the same format and use the same date format symbols as the `datenum` function.

`decyear` does not accept formats containing the letter *Q*.

If `format` does not contain enough information to compute a date number, then:

- Hours, minutes, and seconds default to 0.
- Days default to 1.
- Months default to January.
- Years default to the current year.

Data Types: `char` | `string`

year — Year

current year (default) | scalar | one-dimensional array

Year, specified as a scalar or one-dimensional array.

Dates with two character years are interpreted to be within 100 years of the current year.

Dependencies

Depending on the syntax, specify **year**, **month**, and **day** or **year**, **month**, **day**, **hour**, **minute**, and **second** as one-dimensional arrays of the same length or scalar values.

Data Types: double

month — Month

1 (default) | 2 | 3 | 4 | 5 | 6 | 7 | 8 | 9 | 10 | 11 | 12 | one-dimensional array

Month, specified as a scalar or one-dimensional array from 1 to 12.

Dependencies

Depending on the syntax, specify **year**, **month**, and **day** or **year**, **month**, **day**, **hour**, **minute**, and **second** as one-dimensional arrays of the same length or scalar values.

Data Types: double

day — Day

1 (default) | 2 | 3 | 4 | 5 | 6 | 7 | 8 | 9 | 10 | 11 | 12 | 13 | 14 | 15 | 16 | 17 | 18 | 19 | 20 | 21 | 22 | 23 | 24 | 25 | 26 | 27 | 28 | 29 | 30 | 31 | one-dimensional array

Day, specified as a scalar or one-dimensional array from 1 to 31.

Dependencies

Depending on the syntax, specify **year**, **month**, and **day** or **year**, **month**, **day**, **hour**, **minute**, and **second** as one-dimensional arrays of the same length or scalar values.

Data Types: double

hour — Date format

0 (default) | double, whole number, 0 to 24

Hour, specified as a scalar from 0 to 24.

Dependencies

Depending on the syntax, specify **year**, **month**, and **day** or **year**, **month**, **day**, **hour**, **minute**, and **second** as one-dimensional arrays of the same length or scalar values.

Data Types: double

minute — Minute

0 (default) | double, whole number, 0 to 60

Minute, specified as a double, whole number from 0 to 60.

Dependencies

Depending on the syntax, specify **year**, **month**, and **day** or **year**, **month**, **day**, **hour**, **minute**, and **second** as one-dimensional arrays of the same length or scalar values.

Data Types: double

second — Second

0 (default) | double, whole number, 0 to 60

Second, specified as a double, whole number from 0 to 60.

Dependencies

Depending on the syntax, specify `year`, `month`, and `day` or `year`, `month`, `day`, `hour`, `minute`, and `second` as one-dimensional arrays of the same length or scalar values.

Data Types: `double`

Output Arguments**dy — Decimal year**

column vector

Decimal year, returned as a column vector.

- *m*-by-6 column vector — Contains six elements specifying the year, month, day, hour, minute, and second
- *m*-by-3 column vector — Contains three elements specifying the year, month, and day

Dependencies

The output format depends on the input format:

Input Syntax	dy Format
<code>dy = decyear(dateVector)</code>	<i>m</i> -by-6 column vector or <i>m</i> -by-3 column vector of <i>m</i> decimal years
<code>dy = decyear(dateCharacterVector, format)</code>	Column vector of <i>m</i> decimal years, where <i>m</i> is the number of character vectors in <code>dateCharacterVector</code>

See Also

`datenum` | `datestr` | `decyear` | `leapyear` | `mjuliandate`

Introduced in R2006b

delete

Class: Aero.Animation

Package: Aero

Destroy animation object

Syntax

```
delete(h)  
h.delete
```

Description

`delete(h)` and `h.delete` destroy the animation object `h`. This function also destroys the animation object figure, and any objects that the animation object contained (for example, bodies, camera, and geometry).

Input Arguments

`h` Animation object.

Examples

Delete the animation object, `h`.

```
h=Aero.Animation;  
h.delete;
```

delete (Aero.FlightGearAnimation)

Destroy FlightGear animation object

Syntax

```
delete(h)  
h.delete
```

Description

delete(h) and h.delete destroy the FlightGear animation object h. This function also destroys the animation object timer, and closes the socket that the FlightGear animation object contains.

Examples

Delete the FlightGear animation object, h.

```
h=Aero.FlightGearAnimation;  
h.delete;
```

See Also

initialize

Introduced in R2007a

delete (Aero.VirtualRealityAnimation)

Destroy virtual reality animation object

Syntax

```
delete(h)  
h.delete
```

Description

`delete(h)` and `h.delete` destroy the virtual reality animation object `h`. This function also destroys the temporary file, if it exists, cleans up the `vrfigure` object, the animation object timer, and closes the `vrworld` object.

Examples

Delete the virtual reality animation object, `h`.

```
h=Aero.VirtualRealityAnimation;  
h.delete;
```

See Also

`initialize`

Introduced in R2007b

deltaCIP

Calculate Celestial Intermediate Pole (CIP) location adjustment

Syntax

```
DCIP=deltaCIP(utc)
[DCIP,DCIPError]=deltaCIP(utc)

DCIP=deltaCIP(utc,Name,Value)
[DCIP,DCIPError]=deltaCIP(utc,Name,Value)
```

Description

`DCIP=deltaCIP(utc)` calculates the adjustment to location of the Celestial Intermediate Pole (CIP) for a specific Universal Coordinated Time (UTC), specified as a modified Julian date. By default, this function uses a prepopulated list of IAU 2000A Earth orientation (IERS) data. This list contains measured and calculated (predicted) data supplied by the IERS. The IERS measures and calculates this data for a set of predetermined dates.

`[DCIP,DCIPError]=deltaCIP(utc)` returns the error for the adjustment to location of the CIP.

`DCIP=deltaCIP(utc,Name,Value)` calculates the location of the CIP using additional options specified by one or more `Name, Value` pair arguments.

`[DCIP,DCIPError]=deltaCIP(utc,Name,Value)` returns the error for the adjustment to location of the CIP.

Examples

Calculate CIP Location Adjustment

Calculate the CIP adjustment for December 28, 2015. Use the `mjuliandate` function to calculate the date as a modified Julian date.

```
mjd = mjuliandate(2015,12,28)
dCIP = deltaCIP(mjd)
```

```
mjd =
    57384
dCIP =
    1.0e-09 *
    -0.3927    0.0145
```

Calculate CIP Location Adjustment and Error Using IERS Data

Calculate the CIP adjustment and CIP adjustment error for December 28, 2015 and January 10, 2016 using the `aeroiersdata.mat` file. Use the `mjuliandate` function to calculate the date as a modified Julian date.

```

mjd = mjuliandate([2015 12 28;2016 1 10])
[dCIP,dCIPErr] = deltaCIP(mjd,'Source','aeroiersdata.mat')

mjd =
    57384
    57397
dCIP =
    1.0e-08 *
   -0.0393    0.0015
   -0.0087   -0.1110

dCIPErr =
    1.0e-09 *
    0.5769    0.1842
    0.2376    0.4121

```

Input Arguments

utc — Principal Universal Time (UT1) for UTC

M-by-1 array

Array of UTC dates, specified as an *M*-by-1 array, represented as modified Julian dates. Use the `mjuliandate` function to convert the UTC date to a modified Julian date.

Data Types: `double`

Name-Value Pair Arguments

Specify optional comma-separated pairs of `Name`, `Value` arguments. `Name` is the argument name and `Value` is the corresponding value. `Name` must appear inside quotes. You can specify several name and value pair arguments in any order as `Name1,Value1,...,NameN,ValueN`.

Example: `'Source','aeroiersdata.mat'`

Source — Custom list of Earth orientation data

`aeroiersdata.mat` (default) | MAT-file

Custom list of Earth orientation data, specified in a MAT-file.

action — Out-of-range action

Warning (default) | action

Out-of-range action, specified as a string.

Action to take in case of out-of-range or predicted value dates, specified as a string:

- `Warning` — Displays warning and indicates that the dates were out-of-range or predicted values.
- `Error` — Displays error and indicates that the dates were out-of-range or predicted values.
- `None` — Does not display warning or error.

Data Types: `string`

Output Arguments

DCIP — Adjustment to location of the CIP

M-by-2 array

Adjustment ([dDeltaX, dDeltaY]) to location of the Celestial Intermediate Pole (CIP), specified as an *M*-by-2 array, in radians.

DCIPError — Error for adjustment to location of the CIP

M-by-2 array

Error for adjustment to location of the CIP, specified as an *M*-by-2 array, in radians.

Compatibility Considerations

Updated `aeroiersdata.mat` file

Behavior changed in R2020b

The contents of the `aeroiersdata.mat` file have been updated. Correspondingly, the output of this function will have different results when using the default value ('`aeroiersdata.mat`') as the value of `Source`. The results reflect more accurate external data from the International Earth Rotation and Reference Systems Service (IERS).

See Also

`aeroReadIERSData` | `dcmeCI2ecef` | `deltaUT1` | `eci2aer` | `eci2lla` | `lla2eci` | `mjuliandate` | `polarMotion`

Topics

"Estimate Sun Analemma Using Planetary Ephemerides and ECI to AER Transformation" on page 5-108

Introduced in R2018b

deltaUT1

Calculate difference between Coordinated Universal Time (UTC) and Principal Universal Time (UT1)

Syntax

```
DUT1=deltaUT1(utc)
[DUT1,DUT1Error]=deltaUT1(utc)

DUT1=deltaUT1(utc,Name,Value)
[DUT1,DUT1Error]=deltaUT1(utc,Name,Value)
```

Description

`DUT1=deltaUT1(utc)` calculates the difference between Coordinated Universal Time (UTC) and Principal Universal Time (UT1) for UTC, specified as a modified Julian date (MJD). By default, this function uses a prepopulated list of International Astronomical Union (IAU) 2000A Earth orientation (IERS) data. This list contains measured and calculated (predicted) data supplied by the IERS. The IERS measures and calculates this data for a set of predetermined dates. For dates after those listed in the prepopulated list, `deltaUT1` calculates the data by using this equation, limiting the values to +/- .9s:

$$UT1 - UTC = 0.5309 - 0.00123(MJD - 57808) - (UT2 - UT1)$$

`[DUT1,DUT1Error]=deltaUT1(utc)` returns the error for the difference between Coordinated Universal Time (UTC) and Principal Universal Time (UT1) for UTC.

`DUT1=deltaUT1(utc,Name,Value)` calculates the difference between UTC and UT1 using additional options specified by one or more `Name,Value` pair arguments.

`[DUT1,DUT1Error]=deltaUT1(utc,Name,Value)` returns the error for the difference between Coordinated Universal Time (UTC) and Principal Universal Time (UT1) for UTC.

Examples

Calculate Difference Value for December 28, 2015

Calculate the difference between UT1 and UTC values for December 28, 2015.

```
mjd = mjuliandate(2015,12,28)
dUT1 = deltaUT1(mjd)
```

```
mjd =
    57384
```

```
dUT1 =
    0.0886
```


Calculate Difference Value for December 28, 2015 and January 10, 2016

Calculate the difference between UT1 and UTC values for December 28, 2015 and January 10, 2016 using the custom file, `aeroiersdata20170101.mat`.

```
mjd = m juliandate([2015 12 28;2016 1 10])
dUT1 = deltaUT1(mjd, 'Source', 'aeroiersdata20170101.mat')

mjd =
    57384
    57397

dUT1 =
    0.0886
    0.0648
```

Calculate Difference Value and Error Using IERS Data

Calculate the difference between UT1-UTC values for December 28, 2015 and January 10, 2016 using the custom file, `aeroiersdata.mat`.

```
mjd = m juliandate([2015 12 28;2016 1 10])
[dUT1,dUT1Err] = deltaUT1(mjd, 'Source', 'aeroiersdata.mat')

mjd =
    57384
    57397

dUT1 =
    0.0886
    0.0648

dUT1Err =
    1.0e-05 *

    0.3900
    0.7300
```

Input Arguments

`utc` — Principal Universal Time (UT1) for UTC

M-by-1 array

Array of UTC dates, specified as an *M*-by-1 array, represented as modified Julian dates. Use the `m juliandate` function to convert the UTC date to a modified Julian date.

Name-Value Pair Arguments

Specify optional comma-separated pairs of `Name`, `Value` arguments. `Name` is the argument name and `Value` is the corresponding value. `Name` must appear inside quotes. You can specify several name and value pair arguments in any order as `Name1, Value1, ..., NameN, ValueN`.

Example: `'Source', 'aeroiersdata.mat'`

Source — Custom list of Earth orientation data

`aeroiersdata.mat` (default) | MAT-file

Custom list of Earth orientation data, specified in a MAT-file.

action — Out-of-range action

Warning (default) | action

Out-of-range action, specified as a string.

Action to take in case of out-of-range or predicted value dates, specified as a string:

- Warning — Displays warning and indicates that the dates were out-of-range or predicted values.
- Error — Displays error and indicates that the dates were out-of-range or predicted values.
- None — Does not display warning or error.

Data Types: `string`

Output Arguments**DUT1 — Difference between UT1 and UTC**

M-by-1 array

Difference between UT1 and UTC, specified as an *M*-by-1 array.

DUT1Error — Error for difference between UT1 and UTC

M-by-1 array

Error for difference between UT1 and UTC (UT1-UTC), according to the International Astronomical Union (IAU) 2000A resolutions, specified as an *M*-by-1 array, in seconds.

Compatibility Considerations**Updated `aeroiersdata.mat` file**

Behavior changed in R2020b

The contents of the `aeroiersdata.mat` file have been updated. Correspondingly, the output of this function will have different results when using the default value (`'aeroiersdata.mat'`) as the value of `Source`. The results reflect more accurate external data from the International Earth Rotation and Reference Systems Service (IERS).

See Also

`aeroReadIERSData` | `dcmece2ecef` | `eci2aer` | `eci2lla` | `lla2eci` | `mjuliandate`

Topics

“Estimate Sun Analemma Using Planetary Ephemerides and ECI to AER Transformation” on page 5-108

Introduced in R2017b

dpressure

Compute dynamic pressure using velocity and density

Syntax

```
dynamic_pressure = dpressure(velocity, rho)
```

Description

`dynamic_pressure = dpressure(velocity, rho)` computes dynamic pressure, `dynamic_pressure`, from an m -by-3 array of Cartesian velocity vectors, `velocity`, and a 1-D array of densities, `rho`. `velocity` and `rho` must have the same length units.

Examples

Determine Dynamic Pressure for Velocity in Feet per Second and Density in Slugs per Feet Cubed

Determine dynamic pressure for velocity in feet per second and density in slugs per feet cubed:

```
q = dpressure([84.3905 33.7562 10.1269], 0.0024)
```

```
q =
```

```
10.0365
```

Determine Dynamic Pressure for Velocity in Meters per Second and Density in Kilograms per Meters Cubed

Determine dynamic pressure for velocity in meters per second and density in kilograms per meters cubed:

```
q = dpressure([25.7222 10.2889 3.0867], [1.225 0.3639])
```

```
q =
```

```
475.9252
141.3789
```

Determine Dynamic Pressure for Velocity in Meters per Second and Density in Kilograms per Meters Cubed

Determine dynamic pressure for velocity in meters per second and density in kilograms per meters cubed:

```
q = dpressure([50 20 6; 5 0.5 2], [1.225 0.3639])
```

```
q =  
    1.0e+03 *  
    1.7983  
    0.0053
```

Input Arguments

velocity – Cartesian velocity vectors

m-by-3 array | vector

Cartesian velocity vectors, specified as an *m*-by-3 array. `velocity` and `rho` must have the same length.

Data Types: double

rho – Density

array

Density, specified as an array of *m* densities. `velocity` and `rho` must have the same number of rows.

Data Types: double

Output Arguments

dynamic_pressure – Dynamic pressure

scalar | array

Dynamic pressure, returned as a scalar or array of *m* pressures.

See Also

`airspeed` | `machnumber`

Introduced in R2006b

earthNutation

Implement Earth nutation

Syntax

```
angles= earthNutation(ephemerisTime)
angles= earthNutation(ephemerisTime,ephemerisModel)
angles= earthNutation(ephemerisTime,ephemerisModel,action)
```

```
[angles,rates] = earthNutation( ___ )
```

Description

`angles= earthNutation(ephemerisTime)` implements the International Astronomical Union (IAU) 1980 nutation series for `ephemerisTime`, expressed in Julian days. It returns angles.

The function uses the Chebyshev coefficients that the NASA Jet Propulsion Laboratory provides.

This function requires that you download ephemeris data with the Add-On Explorer. For more information, see `aeroDataPackage`.

`angles= earthNutation(ephemerisTime,ephemerisModel)` uses the `ephemerisModel` coefficients to implement these values.

`angles= earthNutation(ephemerisTime,ephemerisModel,action)` uses `action` to determine error reporting.

`[angles,rates] = earthNutation(___)` implements the International Astronomical Union (IAU) 1980 nutation series using any combination of the input arguments in the previous syntaxes. It returns angles and angular rates.

Examples

Implement Earth Nutation Angles

Implement Earth nutation angles for December 1, 1990. Because no ephemerides model is specified, the default, DE405, is used. Use the `juliandate` function to specify the Julian date.

```
angles = earthNutation(juliandate(1990,12,1))
```

```
angles =
    1.0e-04 *
    0.6448    0.2083
```

Implement Earth Nutation Angles and Angular Rates

Implement Earth nutation angles and angular rates for noon on January 1, 2000 using DE421:

```
[angles,rates] = earthNutation([2451544.5 0.5], '421')
```

```

angles =
    1.0e-04 *
    -0.6750  -0.2799

rates =
    1.0e-07 *
    0.3687  -0.9937

```

Input Arguments

ephemerisTime — Julian date

scalar | 2-element vector | column vector | M -by-2 matrix

Julian dates for which the positions are calculated, specified as one of the following:

- Scalar

Specify one fixed Julian date.

- 2-element vector

Specify the Julian date in multiple parts. The first element is the Julian date for a specific epoch that is the most recent midnight at or before the interpolation epoch. The second element is the fractional part of a day elapsed between the first element and epoch. The second element must be positive. The value of the first element plus the second element cannot exceed the maximum Julian date.

- Column vector

Specify a column vector with M elements, where M is the number of fixed Julian dates.

- M -by-2 matrix

Specify a matrix, where M is the number of Julian dates and the second column contains the elapsed days (Julian epoch date/elapsed day pairs).

Data Types: double

ephemerisModel — Ephemerides coefficients

'405' (default) | '421' | '423' | '430'

Ephemerides coefficients, specified as one of these ephemerides defined by the Jet Propulsion Laboratory:

- '405'

Released in 1998. This ephemerides takes into account the Julian date range 2305424.50 (December 9, 1599) to 2525008.50 (February 20, 2201).

This function calculates these ephemerides with respect to the International Celestial Reference Frame version 1.0, adopted in 1998.

- '421'

Released in 2008. This ephemerides takes into account the Julian date range 2414992.5 (December 4, 1899) to 2469808.5 (January 2, 2050).

This function calculates these ephemerides with respect to the International Celestial Reference Frame version 1.0, adopted in 1998.

- '423'

Released in 2010. This ephemerides takes into account the Julian date range 2378480.5 (December 16, 1799) to 2524624.5 (February 1, 2200).

This function calculates these ephemerides with respect to the International Celestial Reference Frame version 2.0, adopted in 2010.

- '430'

Released in 2013. This ephemerides takes into account the Julian date range 2287184.5 (December 21, 1549) to 2688976.5 (January 25, 2650).

This function implements these ephemerides with respect to the International Celestial Reference Frame version 2.0, adopted in 2010.

Data Types: char

action — Function behavior

'Error' (default) | 'None' | 'Warning'

Function behavior when inputs are out of range, specified as one of these values:

Value	Description
'None'	No action.
'Warning'	Warning in the MATLAB Command Window, model simulation continues.
'Error'	MATLAB returns an exception, model simulation stops.

Data Types: char

Output Arguments

angles — Earth nutation angles

M-by-2 vector

Earth nutation angles, returned as an *M*-by-2 vector, where *M* is the number of Julian dates. The 2 vector contains the $d(\psi)$ and $d(\epsilon)$ angles, in radians. The input arguments include multiple Julian dates or epochs. The vector has the same number of rows as the `ephemerisTime` input.

rates — Earth nutation angular rates

M-by-2 vector

Earth nutation angular rates, returned as an *M*-by-2 vector, where *M* is the number of Julian dates. The 2 vector contains the $d(\psi)$ and $d(\epsilon)$ angular rate, in radians/day. The input arguments include multiple Julian dates or epochs. The vector has the same number of rows as the `ephemerisTime` input.

References

- [1] Folkner, W. M., J. G. Williams, D. H. Boggs, "The Planetary and Lunar Ephemeris DE 421," *JPL Interplanetary Network Progress Report 24-178*, 2009.
- [2] Vallado, D. A., *Fundamentals of Astrodynamics and Applications*, McGraw-Hill, New York, 1997.

See Also

`juliandate` | `moonLibration` | `planetEphemeris`

External Websites

https://ssd.jpl.nasa.gov/?planet_eph_export

Introduced in R2013a

ecef2eci

Position and velocity vectors in Earth-centered inertial mean-equator mean-equinox

Syntax

```
[r_eci] = ecef2eci(utc,r_ecef)
[r_eci,v_eci] = ecef2eci( ____,v_ecef)
[r_eci,v_eci,a_eci] = ecef2eci( ____,a_ecef)
[r_eci,v_eci,a_eci] = ecef2eci( ____,Name,Value)
```

Description

`[r_eci] = ecef2eci(utc,r_ecef)` calculates the position vector in the Earth-centered inertial (ECI) coordinate system for a given position vector in the Earth-centered Earth-fixed (ECEF) coordinate system at a specific Coordinated Universal Time (UTC). For more information on the Earth-centered Earth-fixed coordinate system, see “Algorithms” on page 4-308.

`[r_eci,v_eci] = ecef2eci(____,v_ecef)` calculates the position and velocity vectors for given position and velocity vectors.

`[r_eci,v_eci,a_eci] = ecef2eci(____,a_ecef)` calculates the position, velocity, acceleration vectors for given position, velocity, and acceleration vectors.

`[r_eci,v_eci,a_eci] = ecef2eci(____,Name,Value)` calculates the position, velocity, and acceleration vectors at a higher precision using Earth orientation parameters.

Examples

Convert ECEF Position and Velocity to ECI

Convert the ECEF position and velocity to ECI at 12:00 on January 4, 2019.

```
r_ecef = [-5762640 -1682738 3156028];
v_ecef = [3832 -4024 4837];
utc = [2019 1 4 12 0 0];
[r_eci, v_eci] = ecef2eci(utc, r_ecef, v_ecef);
```

```
r_eci =
    1.0e+06 *
    -2.9818
     5.2070
     3.1616
```

```
v_eci =
    1.0e+03 *
    -3.3837
    -4.8870
     4.8430
```

Convert ECEF Position to ECI Including Polar Motion Effects

Convert the ECEF position to ECI at 12:00 on January 4, 2019, including the effects of polar motion.

```
r_ecef = [-5762640 -1682738 3156028];
utc = [2019 1 4 12 0 0];
mjd = mjuliandate(utc);
pm = polarMotion(mjd, 'action', 'none')*180/pi;
r_eci = ecef2eci(utc, r_ecef, 'pm', pm);
```

```
r_eci =
    1.0e+06 *
    -2.9818
     5.2070
     3.1616
```

Input Arguments

utc — Universal Coordinated Time

1-by-6 array | 1-by-6 matrix

UTC in the order year, month, day, hour, minutes, and seconds, specified as 1-by-6 array of UTC values:

Time Value	Enter
Year	Double value that is a whole number greater than 1, such as 2013.
Month	Double value that is a whole number greater than 0, within the range 1 to 12.
Day	Double value that is a whole number greater than 0, within the range 1 to 31.
Hour	Double value that is a whole number greater than 0, within the range 1 to 24.
Minute and second	Double value that is a whole number greater than 0, within the range 1 to 60.

Example: [2000 1 12 4 52 12.4]

Data Types: double

r_ecef — Position components

3-by-1 array

Array of ECEF position components, specified as a 3-by-1 array.

Data Types: double

v_ecef — Velocity components

3-by-1 array

ECEF velocity components, specified as a 3-by-1 array.

Data Types: double

a_ecef — Acceleration components

3-by-1 array

ECEF acceleration components, specified as a 3-by-1 array.

Data Types: double

Name-Value Pair Arguments

Specify optional comma-separated pairs of **Name**, **Value** arguments. **Name** is the argument name and **Value** is the corresponding value. **Name** must appear inside quotes. You can specify several name and value pair arguments in any order as **Name1**, **Value1**, . . . , **NameN**, **ValueN**.

Example: 'dUT1', 0.234

dAT — Difference between TAI and UTC

0 (default) | scalar

Difference between International Atomic Time (TAI) and UTC, specified as a scalar, in seconds.

Example: 32

Data Types: double

dUT1 — Difference between UTC and Universal Time

0 (default) | scalar

Difference between UTC and Universal Time (UT1), specified as a scalar, in seconds.

Example: 0.234

Data Types: double

pm — Polar displacement

array of zeroes (default) | 1-by-2 array

Polar displacements due to the motion of Earth crust along the x - and y -axis, in degrees.

Tip To calculate the displacement, use the `polarMotion` function.

Example: `pm = polarMotion(mjd, 'action', 'none')*180/pi;`

Data Types: double

dCIP — Adjustment to the CIP location

1-by-2 array

Adjustment to the location of the Celestial Intermediate Pole (CIP), in degrees, specified as a comma-separated pair consisting of **dCIP** and an M -by-2 array. This location ($dDeltaX$, $dDeltaY$) is along the x - and y - axes. By default, this function assumes a 1-by-2 array of zeroes.

For historical values, see the International Earth Rotation and Reference Systems Service Web site (<https://www.iers.org>) and navigate to the Earth orientation data Data/Products page.

- M -by-2 array

Specify an M -by-2 array of location adjustment values, where M is the number of direction cosine or transformation matrices to be converted. Each row corresponds to one set of $dDeltaX$ and $dDeltaY$ values.

Example: [-0.2530e-6 -0.0188e-6]

Data Types: double

lod — Excess length of day

0 (default) | scalar

Excess length of day (difference between astronomically determined duration of day and 86400 SI seconds), specified as a scalar, in seconds.

Example: 32

Data Types: double

Output Arguments

r_eci — Position components

3-by-1 array

ECI position components, specified as a 3-by-1 array.

v_eci — Velocity components

3-by-1 array

ECI velocity components, specified as a 3-by-1 array.

a_eci — Acceleration components

3-by-1 array

ECI acceleration components, specified as a 3-by-1 array.

Algorithms

The `ecef2eci` function uses these Earth-centric coordinate systems:

- Earth Centered Inertial Frame (ECI) — The inertial frame used is the International Celestial Reference Frame (ICRF). This frame can be treated as equal to the ECI coordinate system realized at J2000 (Jan 1 2000 12:00:00 TT). For more information, see “ECI Coordinates” on page 2-7.
- Earth-centered Earth-fixed Frame (ECEF) — The fixed-frame used is the International Terrestrial Reference Frame (ITRF). This reference frame is realized by the IAU2000/2006 reduction from the ICRF coordinate system. For more information, see “ECEF Coordinates” on page 2-8.

References

- [1] Vallado, D. A. *Fundamentals of Astrodynamics and Applications*. alg. 4. New York: McGraw-Hill, 1997.
- [2] Gottlieb, R. G., "Fast Gravity, Gravity Partial, Normalized Gravity, Gravity Gradient Torque and Magnetic Field: Derivation, Code and Data," Technical Report NASA Contractor Report 188243, NASA Lyndon B. Johnson Space Center, Houston, Texas, February 1993.

- [3] Konopliv, A. S., S. W. Asmar, E. Carranza, W. L. Sjogren, D. N. Yuan., "Recent Gravity Models as a Result of the Lunar Prospector Mission, Icarus", Vol. 150, no. 1, pp 1-18, 2001.
- [4] Lemoine, F. G., D. E. Smith, D.D. Rowlands, M.T. Zuber, G. A. Neumann, and D. S. Chinn, "An improved solution of the gravity field of Mars (GMM-2B) from Mars Global Surveyor", Journal Of Geophysical Research, Vol. 106, No. E10, pp 23359-23376, October 25, 2001.
- [5] Seidelmann, P.K., Archinal, B.A., A'hearn, M.F. et al. Report of the IAU/IAG Working Group on cartographic coordinates and rotational elements: 2006. Celestial Mech Dyn Astr 98, 155-180 (2007).

See Also

CubeSat Vehicle | aeroReadIERSData | dcmeci2ecef | deltaCIP | deltaUT1 | eci2ecef | polarMotion | siderealTime

External Websites

Report of the IAU/IAG Working Group on cartographic coordinates and rotational elements: 2006

Introduced in R2019a

ecef2lla

Convert Earth-centered Earth-fixed (ECEF) coordinates to geodetic coordinates

Syntax

```
lla = ecef2lla(ecef)
lla = ecef2lla(ecef,model)
lla = ecef2lla(ecef,f,Re)
```

Description

`lla = ecef2lla(ecef)` converts the m -by-3 array of ECEF coordinates, `ecef`, to an m -by-3 array of geodetic coordinates (latitude, longitude and altitude), `lla`.

`lla = ecef2lla(ecef,model)` converts the coordinates for a specific ellipsoid planet.

`lla = ecef2lla(ecef,f,Re)` converts the coordinates for a custom ellipsoid planet defined by flattening, f , and the equatorial radius, Re .

Examples

Determine Latitude, Longitude, and Altitude at One ECEF Coordinate

Determine latitude, longitude, and altitude at an ECEF coordinate:

```
lla = ecef2lla([4510731 4510731 0])
lla =
    0    45.0000    999.9564
```

Determine Latitude, Longitude, and Altitude at Multiple ECEF Coordinates

Determine latitude, longitude, and altitude at multiple ECEF coordinates with the WGS84 ellipsoid model:

```
lla = ecef2lla([4510731 4510731 0; 0 4507609 4498719], 'WGS84')
lla =
    0    45.0000    999.9564
45.1358    90.0000    999.8659
```

Determine Latitude, Longitude, and Altitude at Multiple ECEF Coordinates with Custom Ellipsoid Model

Determine latitude, longitude, and altitude at multiple coordinates with the custom ellipsoid model:

```
f = 1/196.877360;
Re = 3397000;
lla = ecef2lla([4510731 4510731 0; 0 4507609 4498719], f, Re)

lla =

    1.0e+06 *
           0    0.0000    2.9821
    0.0000    0.0001    2.9801
```

Input Arguments

ecef — ECEF coordinates

m-by-3 array | vector

ECEF coordinates, specified as an *m*-by-3 array.

Data Types: `double`

model — Ellipsoid planet model

'WGS84' (default)

Ellipsoid planet model, specified as 'WGS84'.

Data Types: `double`

f — Flattening

scalar

Flattening at each pole, specified as a scalar.

Data Types: `double`

Re — Equatorial radius

scalar

Equatorial radius, specified as a scalar in meters.

Data Types: `double`

Output Arguments

lla — Geodetic coordinates

m-by-3 array

Geodetic coordinates (latitude, longitude, and altitude), returned as an *m*-by-3 array in [degrees degrees meters].

See Also

`geoc2geod` | `geod2geoc` | `lla2ecef`

Introduced in R2006b

eci2aer

Convert Earth-centered inertial (ECI) coordinates to azimuth, elevation, slant range (AER) coordinates

Syntax

```
aer = eci2aer(position,utc,lla0)
```

```
aer = eci2aer(position,utc,lla0,reduction)
```

```
aer = eci2aer(position,utc,lla0,reduction,deltaAT)
```

```
aer = eci2aer(position,utc,lla0,reduction,deltaAT,deltaUT1)
```

```
aer = eci2aer(position,utc,lla0,reduction,deltaAT,deltaUT1,polarmotion)
```

```
aer = eci2aer(position,utc,lla0,reduction,deltaAT,deltaUT1,polarmotion,
Name,Value)
```

Description

`aer = eci2aer(position,utc,lla0)` converts Earth-centered inertial coordinates, specified by `position`, to azimuth, elevation, and slant range (AER) coordinates, based on the geodetic position (latitude, longitude, and altitude). The conversion is based on the Universal Coordinated Time (UTC) you specify.

- Azimuth (A) — Angle measured clockwise from true north. It ranges from 0 to 360 degrees.
- Elevation (E) — Angle between a plane perpendicular to the ellipsoid and the line that goes from the local reference to the object position. It ranges from -90 to 90 degrees.
- Slant range (R) — Straight line distance between the local reference and the object, meters.

`aer = eci2aer(position,utc,lla0,reduction)` converts Earth-centered inertial coordinates, specified by `position`, to azimuth, elevation, and slant range coordinates. The conversion is based on the specified reduction method and the Universal Coordinated Time you specify.

`aer = eci2aer(position,utc,lla0,reduction,deltaAT)` uses the difference between International Atomic Time and UTC that you specify as `deltaAT` to calculate the AER coordinates.

`aer = eci2aer(position,utc,lla0,reduction,deltaAT,deltaUT1)` uses the difference between UTC and Universal Time (UT1), which you specify as `deltaUT1`, in the calculation.

`aer = eci2aer(position,utc,lla0,reduction,deltaAT,deltaUT1,polarmotion)` uses the polar displacement, `polarmotion`, in the calculation.

`aer = eci2aer(position,utc,lla0,reduction,deltaAT,deltaUT1,polarmotion, Name,Value)` uses additional options specified by one or more `Name,Value` pair arguments.

Examples

Convert Position to AER Coordinates Using UTC

Convert the position to AER coordinates from ECI coordinates $1e08*[-3.8454 -0.5099 -0.3255]$ meters for the date 1969/7/20 21:17:40 UTC at 28.4 degrees north, 80.5 degrees west and 2.7 meters altitude.

```
aer = eci2aer(1e08*[-3.8454, -0.5099, -0.3255], ...
[1969, 7, 20, 21, 17, 40], [28.4, -80.5, 2.7])
```

```
aer =
```

```
1.0e+08 *
0.0000    0.0000    3.8401
```

Convert Position to AER Coordinates Using UTC and Reduction Method IAU-76/FK5

Convert the position to AER coordinates from ECI coordinates $1e08*[-3.8454 -0.5099 -0.3255]$ meters for the date 1969/7/20 21:17:40 UTC at 28.4 degrees north, 80.5 degrees west and 2.7 meters altitude. For an ellipsoid with a flattening of 1/290 and an equatorial radius of 60000 meters, use the IAU-76/FK5 reduction, polar motion $[-0.0682e-5 \ 0.1616e-5]$ radians, and nutation angles $[-0.2530e-6 -0.0188e-6]$.

```
aer = eci2aer(1e08*[-3.8454, -0.5099, -0.3255], ...
[1969, 7, 20, 21, 17, 40], [28.4, -80.5, 2.7], ...
'IAU-76/FK5', 32, 0.234, [-0.0682e-5 0.1616e-5], ...
'dNutation', [-0.2530e-6 -0.0188e-6], ...
'flattening', 1/290, 'RE', 60000)
```

```
aer =
```

```
1.0e+08 *
0.0000    0.0000    3.8922
```

Input Arguments

position — ECI coordinates

M-by-3 array

ECI coordinates in meters, specified as an *M*-by-3 array.

utc — Universal Coordinated Time

1-by-6 array of whole numbers | *M*-by-6 matrix of whole numbers

Universal Coordinated Time (UTC), in the order year, month, day, hour, minutes, and seconds, for which the function calculates the conversion, specified as one of the following:

- For the year value, enter a double value that is a whole number greater than 1, such as 2013.
- For the month value, enter a double value that is a whole number greater than 0, within the range 1 to 12.
- For the hour value, enter a double value that is a whole number greater than 0, within the range 1 to 24.

- For the hour value, enter a double value that is a whole number greater than 0, within the range 1 to 60.
- For the minute and second values, enter a double value that is a whole number greater than 0, within the range 1 to 60.

Specify these values in one of the following formats:

- 1-by-6 array

Specify a 1-row-by-6-column array of UTC values.

- M -by-6 matrix

Specify an M -by-6 array of UTC values, where M is the number of transformation matrices to calculate. Each row corresponds to one set of UTC values.

This example is a one-row-by-6-column array of UTC values.

Example: [2000 1 12 4 52 12.4]

This example is an M -by-6 array of UTC values, where M is 2.

Example: [2000 1 12 4 52 12.4;2010 6 5 7 22 0]

Data Types: double

lla0 – Geodetic coordinates

M -by-3 array

Geodetic coordinates of the local reference (latitude, longitude, and ellipsoidal altitude), in degrees, degrees, and meters. Latitude and longitude values can be any value. However, latitude values of +90 and -90 can return unexpected values because of singularity at the poles.

reduction – Reduction method

'IAU-2000/2006' (default) | 'IAU-76/FK5'

Reduction method to calculate the coordinate conversion, specified as one of the following:

- 'IAU-76/FK5'

Reduce the calculation using the International Astronomical Union (IAU)-76/Fifth Fundamental Catalogue (FK5) (IAU-76/FK5) reference system. Choose this reduction method if the reference coordinate system for the conversion is FK5. You can use the 'dNutation' Name,Value pair with this reduction.

Note This method uses the IAU 1976 precession model and the IAU 1980 theory of nutation to reduce the calculation. This model and theory are no longer current, but the software provides this reduction method for existing implementations. Because of the polar motion approximation that this reduction method uses, `eci2aer` performs a coordinate conversion that is not orthogonal due to the polar motion approximation.

- 'IAU-2000/2006'

Reduce the calculation using the International Astronomical Union (IAU)-2000/2005 reference system. Choose this reduction method if the reference coordinate system for the conversion is IAU-2000. This reduction method uses the P03 precession model to reduce the calculation. You can use the 'dCIP' Name,Value pair with this reduction.

deltaAT — Difference between International Atomic Time and UTC

scalar | one-dimensional array

Difference between International Atomic Time (IAT) and UTC, in seconds, for which the function calculates the direction cosine or transformation matrix. By default, the function assumes an M -by-1 array of zeroes.

- scalar

Specify one difference-time value to calculate one direction cosine or transformation matrix.

- one-dimensional array

Specify a one-dimensional array with M elements, where M is the number of direction cosine or transformation matrices to calculate. Each row corresponds to one set of UTC values.

Example: 32

Specify 32 seconds as the difference between IAT and UTC.

Data Types: double

deltaUT1 — Difference between UTC and Universal Time (UT1)

scalar | one-dimensional array

Difference between UTC and Universal Time (UT1) in seconds, for which the function calculates the direction cosine or transformation matrix. By default, the function assumes an M -by-1 array of zeroes.

- scalar

Specify one difference-time value to calculate one direction cosine or transformation matrix.

- one-dimensional array

Specify a one-dimensional array with M elements of difference time values, where M is the number of direction cosine or transformation matrices to be calculated. Each row corresponds to one set of UTC values.

Example: 0.234

Specify 0.234 seconds as the difference between UTC and UT1.

Data Types: double

polarmotion — Polar displacement1-by-2 array | M -by-2 array

Polar displacement of the Earth, in radians, from the motion of the Earth crust, along the x - and y -axes. By default, the function assumes an M -by-2 array of zeroes.

- 1-by-2 array

Specify a 1-by-2 array of the polar displacement values to convert one direction cosine or transformation matrix.

- M -by-2 array

Specify an M -by-2 array of polar displacement values, where M is the number of direction cosine or transformation matrices to convert. Each row corresponds to one set of UTC values.

Example: [-0.0682e-5 0.1616e-5]

Data Types: double

Name-Value Pair Arguments

Specify optional comma-separated pairs of *Name*, *Value* arguments. *Name* is the argument name and *Value* is the corresponding value. *Name* must appear inside quotes. You can specify several name and value pair arguments in any order as *Name1*, *Value1*, . . . , *NameN*, *ValueN*.

Example: 'dNutation', [-0.2530e-6 -0.0188e-6]

dNutation — Adjustment to longitude (*dDeltaPsi*) and obliquity (*dDeltaEpsilon*)

M-by-2 array of zeroes (default) | *M*-by-2 array

Adjustment to the longitude (*dDeltaPsi*) and obliquity (*dDeltaEpsilon*), in radians, specified as the comma-separated pair consisting of 'dNutation' and an *M*-by-2 array. You can use this *Name*, *Value* pair with the IAU-76/FK5 reduction.

For historical values, see the International Earth Rotation and Reference Systems Service website (<https://www.iers.org>) and navigate to the Earth Orientation Data Data/Products page.

- *M*-by-2 array

Specify *M*-by-2 array of adjustment values, where *M* is the number of LLA coordinates to be converted. Each row corresponds to one set of longitude and obliquity values.

Data Types: double

dCIP — Adjustment to the location of the celestial intermediate pole (CIP)

M-by-2 array of zeroes (default)

Adjustment to the location of the celestial intermediate pole (CIP), in radians, specified as the comma-separated pair consisting of 'dCIP' and an *M*-by-2 array. This location (*dDeltaX*, *dDeltaY*) is along the *x*- and *y*- axes. You can use this argument with the IAU-200/2006 reduction.

For historical values, see the International Earth Rotation and Reference Systems Service website (<https://www.iers.org>) and navigate to the Earth Orientation Data Data/Products page.

- *M*-by-2 array

Specify *M*-by-2 array of location adjustment values, where *M* is the number of LLA coordinates to convert. Each row corresponds to one set of *dDeltaX* and *dDeltaY* values.

Example: 'dCIP', [-0.2530e-6 -0.0188e-6]

Data Types: double

flattening — Custom ellipsoid planet

1-by-1 array

Custom ellipsoid planet defined by flattening, specified as the comma-separated pair consisting of 'flattening' and a 1-by-1 array.

Example: 1/290

Data Types: double

re – Custom planet ellipsoid radius

1-by-1 array

Custom planet ellipsoid radius, in meters, specified as the comma-separated pair consisting of 're' and a 1-by-1 array.

Example: 60000

Data Types: double

See Also

dcmeci2ecef | ecef2lla | geoc2geod | geod2geoc | lla2ecef | lla2eci

Introduced in R2015a

eci2ecef

Position, velocity, and acceleration vectors in Earth-centered Earth-fixed (ECEF) coordinate system

Syntax

```
[r_ecef,v_ecef,a_ecef] = eci2ecef(utc,r_eci,v_eci,a_eci)
[r_ecef,v_ecef,a_ecef] = eci2ecef(utc,r_eci,v_eci,a_eci,Name,Value)
```

Description

`[r_ecef,v_ecef,a_ecef] = eci2ecef(utc,r_eci,v_eci,a_eci)` calculates position, velocity, and acceleration vectors in Earth-centered Earth-fixed (ECEF) coordinate system for given position, velocity, and acceleration vectors in the Earth-centered inertial (ECI) coordinate system at a specific Coordinated Universal Time (UTC). For more information on the Earth-centered Earth-fixed coordinate system, see “Algorithms” on page 4-321.

`[r_ecef,v_ecef,a_ecef] = eci2ecef(utc,r_eci,v_eci,a_eci,Name,Value)` calculates the position, velocity, and acceleration vectors at a higher precision using Earth orientation parameters.

Examples

Convert ECI Position and Velocity to ECEF

Convert ECI position and velocity to ECEF at 12:00 on January 4, 2019.

```
r_eci = [-2981784 5207055 3161595];
v_eci = [-3384 -4887 4843];
utc = [2019 1 4 12 0 0];
[r_ecef, v_ecef] = eci2ecef(utc, r_eci, v_eci)
```

```
r_ecef =
    1.0e+06 *
    -5.7627
    -1.6827
     3.1560
```

```
v_ecef =
    1.0e+03 *
     3.8319
    -4.0243
     4.8370
```

Convert ECI Position to ECEF Including Polar Motion Effects

Convert ECI position to ECEF at 12:00 on January 4, 2019 including effects of polar motion.

```
r_eci = [-2981784 5207055 3161595];
utc = [2019 1 4 12 0 0];
```

```

mjd = mjuliandate(utc);
pm = polarMotion(mjd, 'action', 'none')*180/pi;
r_ecef = eci2ecef(utc, r_eci, 'pm', pm)

r_ecef =
    1.0e+06 *
    -5.7627
    -1.6827
     3.1560

```

Input Arguments

utc — Universal Coordinated Time

1-by-6 array | 1-by-6 matrix

Universal Coordinated Time (UTC) in the order year, month, day, hour, minutes, and seconds, specified as 1-by-6 array of UTC values:

Time Value	Enter
Year	Double value that is a whole number greater than 1, such as 2013.
Month	Double value that is a whole number greater than 0, within the range 1 to 12.
Day	Double value that is a whole number greater than 0, within the range 1 to 31.
Hour	Double value that is a whole number greater than 0, within the range 1 to 24.
Minute and second	Double value that is a whole number greater than 0, within the range 1 to 60.

Example: [2000 1 12 4 52 12.4]

Data Types: double

r_eci — Position components

3-by-1 array

ECI position components, specified as a 3-by-1 array.

Data Types: double

v_eci — Velocity components

3-by-1 array

ECI velocity components, specified as a 3-by-1 array.

Data Types: double

a_eci — Acceleration components

3-by-1 array

ECI acceleration components, specified as a 3-by-1 array.

Data Types: double

Name-Value Pair Arguments

Specify optional comma-separated pairs of `Name`, `Value` arguments. `Name` is the argument name and `Value` is the corresponding value. `Name` must appear inside quotes. You can specify several name and value pair arguments in any order as `Name1, Value1, ..., NameN, ValueN`.

Example: `'dUT1', 0.234`

dAT — Difference between TAI and UTC

0 (default) | scalar

Difference between International Atomic Time (TAI) and UTC, specified as a scalar, in seconds.

Example: 32

Data Types: double

dUT1 — Difference between UTC and Universal Time

0 (default) | scalar

Difference between UTC and Universal Time (UT1), specified as a scalar, in seconds.

Example: 0.234

Data Types: double

pm — Polar displacement

array of zeroes (default) | 1-by-2 array

Polar displacements due to the motion of Earth crust along the x - and y -axis, in degrees.

Tip To calculate the displacement, use the `polarMotion` function.

Example: `pm = polarMotion(mjd, 'action', 'none')*180/pi;`

Data Types: double

dCIP — Adjustment to the CIP

1-by-2 array

Adjustment to the location of the Celestial Intermediate Pole (CIP), in degrees, specified as a comma-separated pair consisting of `dCIP` and an M -by-2 array. This location ($dDeltaX$, $dDeltaY$) is along the x - and y - axes. By default, this function assumes a 1-by-2 array of zeroes.

For historical values, see the International Earth Rotation and Reference Systems Service Web site (<https://www.iers.org>) and navigate to the Earth Orientation Data Data/Products page.

- M -by-2 array

Specify a M -by-2 array of location adjustment values, where M is the number of direction cosine or transformation matrices to be converted. Each row corresponds to one set of $dDeltaX$ and $dDeltaY$ values.

Example: `[-0.2530e-6 -0.0188e-6]`

Data Types: double

Lod — Excess length of day

0 (default) | scalar

Excess length of day (difference between astronomically determined duration of day and 86400 SI seconds), specified as a scalar, in seconds.

Example: 32

Data Types: double

Output Arguments**r_ecef — Position components**

3-by-1 array

ECEF position components, specified as a 3-by-1 array.

v_ecef — Velocity components

3-by-1 array

ECEF velocity components, specified as a 3-by-1 array.

a_ecef — Acceleration components

3-by-1 array

ECEF acceleration components, specified as a 3-by-1 array.

Algorithms

The `eci2ecef` function uses these Earth-centric coordinate systems:

- Earth Centered Inertial Frame (ECI) — The inertial frame used is the International Celestial Reference Frame (ICRF). This frame can be treated as equal to the ECI coordinate system realized at J2000 (Jan 1 2000 12:00:00 TT). For more information, see “ECI Coordinates” on page 2-7.
- Earth-centered Earth-fixed Frame (ECEF) — The fixed-frame used is the International Terrestrial Reference Frame (ITRF). This reference frame is realized by the IAU2000/2006 reduction from the ICRF coordinate system. For more information, see “ECEF Coordinates” on page 2-8.

References

- [1] Vallado, D. A. *Fundamentals of Astrodynamics and Applications*. alg. 4. New York: McGraw-Hill, 1997.
- [2] Gottlieb, R. G., "Fast Gravity, Gravity Partial, Normalized Gravity, Gravity Gradient Torque and Magnetic Field: Derivation, Code and Data," Technical Report NASA Contractor Report 188243, NASA Lyndon B. Johnson Space Center, Houston, Texas, February 1993.
- [3] Konopliv, A. S., S. W. Asmar, E. Carranza, W. L. Sjogren, D. N. Yuan., "Recent Gravity Models as a Result of the Lunar Prospector Mission, Icarus", Vol. 150, no. 1, pp 1-18, 2001.
- [4] Lemoine, F. G., D. E. Smith, D.D. Rowlands, M.T. Zuber, G. A. Neumann, and D. S. Chinn, "An improved solution of the gravity field of Mars (GMM-2B) from Mars Global Surveyor", Journal Of Geophysical Research, Vol. 106, No. E10, pp 23359-23376, October 25, 2001.

[5] Seidelmann, P.K., Archinal, B.A., A'hearn, M.F. et al. Report of the IAU/IAG Working Group on cartographic coordinates and rotational elements: 2006. *Celestial Mech Dyn Astr* 98, 155-180 (2007).

See Also

CubeSat Vehicle | `aeroReadIERSData` | `dcmeCi2ecef` | `deltaCIP` | `deltaUT1` | `ecef2eci` | `polarMotion` | `siderealTime`

External Websites

Report of the IAU/IAG Working Group on cartographic coordinates and rotational elements: 2006

Introduced in R2019a

eci2lla

Convert Earth-centered inertial (ECI) coordinates to latitude, longitude, altitude (LLA) geodetic coordinates

Syntax

```
lla = eci2lla(position,utc)
```

```
lla = eci2lla(position,utc,reduction)
```

```
lla = eci2lla(position,utc,reduction,deltaAT)
```

```
lla = eci2lla(position,utc,reduction,deltaAT,deltaUT1)
```

```
lla = eci2lla(position,utc,reduction,deltaAT,deltaUT1,polarmotion)
```

```
lla = eci2lla(position,utc,reduction,deltaAT,deltaUT1,polarmotion,Name,Value)
```

Description

`lla = eci2lla(position,utc)` converts Earth-centered inertial (ECI) coordinates, specified by `position`, to latitude, longitude, altitude (LLA) geodetic coordinates. The conversion is based on the Universal Coordinated Time (UTC) you specify.

`lla = eci2lla(position,utc,reduction)` converts Earth-centered inertial (ECI) coordinates, specified by `position`, to latitude, longitude, altitude (LLA) geodetic coordinates. The conversion is based on the specified reduction method and the Universal Coordinated Time (UTC) you specify.

`lla = eci2lla(position,utc,reduction,deltaAT)` uses the difference between International Atomic Time and UTC that you specify as `deltaAT` to calculate the ECI coordinates.

`lla = eci2lla(position,utc,reduction,deltaAT,deltaUT1)` uses the difference between UTC and Universal Time (UT1), which you specify as `deltaUT1`, in the calculation.

`lla = eci2lla(position,utc,reduction,deltaAT,deltaUT1,polarmotion)` uses the polar displacement, `polarmotion`, in the calculation.

`lla = eci2lla(position,utc,reduction,deltaAT,deltaUT1,polarmotion,Name,Value)` uses additional options specified by one or more `Name,Value` pair arguments.

Examples

Convert Position to LLA Coordinates Using UTC

Convert the position to LLA coordinates from ECI coordinates [-6.07 -1.28 0.66]*1e6 at 01/17/2010 10:20:36 UTC.

```
lla = eci2lla([-6.07 -1.28 0.66]*1e6,[2010 1 17 10 20 36])
```

```
lla =
```

```
1.0e+05 *
```

```
0.0001 -0.0008 -1.3940
```

Convert Position to LLA Coordinates Using UTC and Reduction Method IAU-76/FK5

Convert the position to LLA coordinates from ECI coordinates $[-1.1 \ 3.2 \ -4.9] \times 10^4$ at 01/12/2000 4:52:12.4 UTC, with a difference of 32 seconds between TAI and UTC, and 0.234 seconds between UTC and UT1. For an ellipsoid with a flattening of 1/290 and an equatorial radius of 60000 meters, use the IAU-76/FK5 reduction, polar motion $[-0.0682 \times 10^{-5} \ 0.1616 \times 10^{-5}]$ radians, and nutation angles $[-0.2530 \times 10^{-6} \ -0.0188 \times 10^{-6}]$.

```
lla = eci2lla([-1.1 3.2 -4.9]*1e4, [2000 1 12 4 52 12.4], ...
'IAU-76/FK5', 32, 0.234, [-0.0682e-5 0.1616e-5], 'dNutation' ...
, [-0.2530e-6 -0.0188e-6], ...
'flattening', 1/290, 'RE', 60000)
```

```
lla =
```

```
-55.5592 -75.0892 -311.3709
```

Input Arguments

position — ECI coordinates

M-by-3 array

ECI coordinates in meters, specified as an *M*-by-3 array.

utc — Universal Coordinated Time

1-by-6 array | *M*-by-6 matrix

Universal Coordinated Time (UTC), in the order year, month, day, hour, minutes, and seconds, for which the function calculates the conversion, specified as one of the following:

- For the year value, enter a double value that is a whole number greater than 1, such as 2013.
- For the month value, enter a double value that is a whole number greater than 0, within the range 1 to 12.
- For the hour value, enter a double value that is a whole number greater than 0, within the range 1 to 24.
- For the hour value, enter a double value that is a whole number greater than 0, within the range 1 to 60.
- For the minute and second values, enter a double value that is a whole number greater than 0, within the range 1 to 60.

Specify these values in one of the following formats:

- 1-by-6 array

Specify a 1-row-by-6-column array of UTC values.

- *M*-by-6 matrix

Specify an *M*-by-6 array of UTC values, where *M* is the number of transformation matrices to calculate. Each row corresponds to one set of UTC values.

This is a one row-by-6 column array of UTC values.

Example: [2000 1 12 4 52 12.4]

This is an M -by-6 array of UTC values, where M is 2.

Example: [2000 1 12 4 52 12.4;2010 6 5 7 22 0]

Data Types: double

reduction – Reduction method

'IAU-2000/2006' (default) | 'IAU-76/FK5'

Reduction method to calculate the coordinate conversion, specified as one of the following:

- 'IAU-76/FK5'

Reduce the calculation using the International Astronomical Union (IAU)-76/Fifth Fundamental Catalogue (FK5) (IAU-76/FK5) reference system. Choose this reduction method if the reference coordinate system for the conversion is FK5. You can use the 'dNutation' Name,Value pair with this reduction.

Note This method uses the IAU 1976 precession model and the IAU 1980 theory of nutation to reduce the calculation. This model and theory are no longer current, but the software provides this reduction method for existing implementations. Because of the polar motion approximation that this reduction method uses, `eci2lla` performs a coordinate conversion that is not orthogonal because of the polar motion approximation.

- 'IAU-2000/2006'

Reduce the calculation using the International Astronomical Union (IAU)-2000/2005 reference system. Choose this reduction method if the reference coordinate system for the conversion is IAU-2000. This reduction method uses the P03 precession model to reduce the calculation. You can use the 'dCIP' Name,Value pair with this reduction.

deltaAT – Difference between International Atomic Time and UTC

M -by-1 array of zeroes (default) | scalar | one-dimensional array

Difference between International Atomic Time (IAT) and UTC, in seconds, for which the function calculates the coordinate conversion.

- scalar

Specify difference-time value to calculate one direction cosine or transformation matrix.

- one-dimensional array

Specify a one-dimensional array with M elements, where M is the number of ECI coordinates. Each row corresponds to one set of ECI coordinates.

Specify 32 seconds as the difference between IAT and UTC.

Example: 32

Data Types: double

deltaUT1 – Difference between UTC and Universal Time (UT1)

M -by-1 array of zeroes (default) | scalar | one-dimensional array

Difference between UTC and Universal Time (UT1), in seconds, for which the function calculates the coordinate conversion.

- scalar

Specify difference-time value to calculate ECI coordinates.

- one-dimensional array

Specify a one-dimensional array with M elements of difference time values, where M is the number of ECI coordinates. Each row corresponds to one set of ECI coordinates.

Specify 0.234 seconds as the difference between UTC and UT1.

Example: 0.234

Data Types: double

polarmotion — Polar displacement

M -by-2 array of zeroes (default) | 1-by-2 array | M -by-2 array

Polar displacement of the Earth, in radians, from the motion of the Earth crust, along the x - and y -axes.

- 1-by-2 array

Specify a 1-by-2 array of the polar displacement values to convert one ECI coordinate.

- M -by-2 array

Specify an M -by-2 array of polar displacement values, where M is the number of ECI coordinates to convert. Each row corresponds to one set of UTC values.

Example: [-0.0682e-5 0.1616e-5]

Data Types: double

Name-Value Pair Arguments

Specify optional comma-separated pairs of `Name`, `Value` arguments. `Name` is the argument name and `Value` is the corresponding value. `Name` must appear inside quotes. You can specify several name and value pair arguments in any order as `Name1, Value1, ..., NameN, ValueN`.

Example: 'dNutation', [-0.2530e-6 -0.0188e-6]

dNutation — Adjustment to longitude (*dDeltaPsi*) and obliquity (*dDeltaEpsilon*)

M -by-2 array of zeroes (default) | M -by-2 array

Adjustment to the longitude (*dDeltaPsi*) and obliquity (*dDeltaEpsilon*), in radians, specified as the comma-separated pair consisting of `dNutation` and an M -by-2 array. You can use this `Name, Value` pair with the IAU-76/FK5 reduction.

For historical values, see the International Earth Rotation and Reference Systems Service website (<https://www.iers.org>) and navigate to the Earth Orientation Data Data/Products page.

- M -by-2 array

Specify M -by-2 array of adjustment values, where M is the number of LLA coordinates to be converted. Each row corresponds to one set of longitude and obliquity values.

Data Types: double

dCIP — Adjustment to the location of the celestial intermediate pole (CIP)

M-by-2 array of zeroes (default)

Adjustment to the location of the celestial intermediate pole (CIP), in radians, specified as the comma-separated pair consisting of *dCIP* and an *M*-by-2 array. This location (*dDeltaX*, *dDeltaY*) is along the *x*- and *y*- axes. You can use this argument with the IAU-200/2006 reduction.

For historical values, see the International Earth Rotation and Reference Systems Service website (<https://www.iers.org>) and navigate to the Earth Orientation Data Data/Products page.

- *M*-by-2 array

Specify *M*-by-2 array of location adjustment values, where *M* is the number of LLA coordinates to convert. Each row corresponds to one set of *dDeltaX* and *dDeltaY* values.

Example: 'dcip', [-0.2530e-5 -0.0188e-4]

Data Types: double

flattening — Custom ellipsoid planet

1-by-1 array

Custom ellipsoid planet defined by flattening.

Example: 1/290

Data Types: double

re — Custom planet ellipsoid radius

1-by-1 array

Custom planet ellipsoid radius, in meters.

Example: 60000

Data Types: double

See Also

dcmece2ecef | ecef2lla | geoc2geod | geod2geoc | lla2ecef | lla2eci

Introduced in R2014a

EGTIndicator Properties

Control exhaust gas temperature (EGT) indicator appearance and behavior

Description

EGT indicators are components that represent an EGT indicator. Properties control the appearance and behavior of an EGT indicator. Use dot notation to refer to a particular object and property:

```
f = uifigure;
egtindicator = uiaeroegt(f);
egtindicator.Value = 100;
```

The EGT indicator displays temperature measurements for engine exhaust gas temperature (EGT) in Celsius.

This gauge displays values using both:

- A needle on a gauge. A major tick is $(Maximum-Minimum)/1,000$ degrees, a minor tick is $(Maximum-Minimum)/200$ degrees Celsius.
- A numeric indicator. The operating range for the indicator goes from *Minimum* to *Maximum* degrees Celsius.

If the value of the signal is under *Minimum*, the needle displays 5 degrees under the *Minimum* value, the numeric display shows the *Minimum* value. If the value exceeds the *Maximum* value, the needle displays 5 degrees over the maximum tick, and the numeric displays the *Maximum* value.

Properties

EGT Indicator

Limits — Minimum and maximum indicator scale values

[0 1000] (default) | two-element finite, real, and scalar numeric vector

Minimum and maximum indicator scale values, specified as a two-element numeric vector. The first value in the vector must be less than the second value, in degrees Celsius.

If you change **Limits** such that the **Value** property is less than the new lower limit, or more than the new upper limit, then the indicator needle points to a location off the scale.

For example, suppose **Limits** is [0 100] and the **Value** property is 20. If the **Limits** changes to [50 100], then the needle points to a location off the scale, slightly less than 50.

ScaleColors — Scale colors

[] (default) | 1-by-n string array | 1-by-n cell array | n-by-3 array of RGB triplets | hexadecimal color code | ...

Scale colors, specified as one of the following arrays:






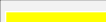


- A 1-by-n string array of color options, such as ["blue" "green" "red"].

- An n-by-3 array of RGB triplets, such as `[0 0 1;1 1 0]`.
- A 1-by-n cell array containing RGB triplets, hexadecimal color codes, or named color options. For example, `{'#EDB120', '#7E2F8E', '#77AC30'}`.








RGB triplets and hexadecimal color codes are useful for specifying custom colors.

- An RGB triplet is a three-element row vector whose elements specify the intensities of the red, green, and blue components of the color. The intensities must be in the range `[0, 1]`; for example, `[0.4 0.6 0.7]`.
- A hexadecimal color code is a character vector or a string scalar that starts with a hash symbol (`#`) followed by three or six hexadecimal digits, which can range from `0` to `F`. The values are not case sensitive. Thus, the color codes `'#FF8800'`, `'#ff8800'`, `'#F80'`, and `'#f80'` are equivalent.

Alternatively, you can specify some common colors by name. This table lists the named color options, the equivalent RGB triplets, and hexadecimal color codes.

Color Name	Short Name	RGB Triplet	Hexadecimal Color Code	Appearance
'red'	'r'	[1 0 0]	'#FF0000'	
'green'	'g'	[0 1 0]	'#00FF00'	
'blue'	'b'	[0 0 1]	'#0000FF'	
'cyan'	'c'	[0 1 1]	'#00FFFF'	
'magenta'	'm'	[1 0 1]	'#FF00FF'	
'yellow'	'y'	[1 1 0]	'#FFFF00'	
'black'	'k'	[0 0 0]	'#000000'	
'white'	'w'	[1 1 1]	'#FFFFFF'	

Here are the RGB triplets and hexadecimal color codes for the default colors MATLAB uses in many types of plots.

RGB Triplet	Hexadecimal Color Code	Appearance
[0 0.4470 0.7410]	'#0072BD'	
[0.8500 0.3250 0.0980]	'#D95319'	
[0.9290 0.6940 0.1250]	'#EDB120'	
[0.4940 0.1840 0.5560]	'#7E2F8E'	
[0.4660 0.6740 0.1880]	'#77AC30'	
[0.3010 0.7450 0.9330]	'#4DBEEE'	
[0.6350 0.0780 0.1840]	'#A2142F'	

Each color of the `ScaleColors` array corresponds to a colored section of the gauge. Set the `ScaleColorLimits` property to map the colors to specific sections of the gauge.

If you do not set the `ScaleColorLimits` property, MATLAB distributes the colors equally over the range of the gauge.

ScaleColorLimits — Scale color limits

`[]` (default) | n-by-2 array

Scale color limits, specified as an n-by-2 array of numeric values. For every row in the array, the first element must be less than the second element.

When applying colors to the indicator, MATLAB applies the colors starting with the first color in the `ScaleColors` array. Therefore, if two rows in `ScaleColorLimits` array overlap, then the color applied later takes precedence.

The indicator does not display any portion of the `ScaleColorLimits` that falls outside of the `Limits` property.

If the `ScaleColors` and `ScaleColorLimits` property values are different sizes, then the indicator shows only the colors that have matching limits. For example, if the `ScaleColors` array has three colors, but the `ScaleColorLimits` has only two rows, then the indicator displays the first two color/limit pairs only.

Temperature — Temperature value

0 (default) | finite, real, and scalar numeric

Temperature value, specified as any finite and scalar numeric, in degrees Celsius

Example: 10

Dependencies

Specifying this value changes the value of `Value`. Conversely, changing `Value` changes the `Temperature` value.

Value — Temperature value

0 (default) | finite, real, and scalar numeric

Temperature value, specified as any finite and scalar numeric, in degrees Celsius.

Example: 10

Dependencies

Specifying this value changes the value of `Temperature`. Conversely, changing `Temperature` changes the `Value` value.

Interactivity

Visible — Visibility of EGT indicator

'on' (default) | on/off logical value

Visibility of the EGT indicator, specified as 'on' or 'off', or as numeric or logical 1 (true) or 0 (false). A value of 'on' is equivalent to true, and 'off' is equivalent to false. Thus, you can use the value of this property as a logical value. The value is stored as an on/off logical value of type `matlab.lang.OnOffSwitchState`. The `Visible` property determines whether the EGT indicator, is displayed on the screen. If the `Visible` property is set to 'off', then the entire EGT indicator is hidden, but you can still specify and access its properties.

ContextMenu — Context menu

empty `GraphicsPlaceholder` array (default) | `ContextMenu` object

Context menu, specified as a `ContextMenu` object created using the `uicontextmenu` function. Use this property to display a context menu when you right-click on a component.

Enable — Operational state of EGT indicator

'on' (default) | on/off logical value

Operational state of EGT indicator, specified as 'on' or 'off', or as numeric or logical 1 (true) or 0 (false). A value of 'on' is equivalent to true, and 'off' is equivalent to false. Thus, you can use the value of this property as a logical value. The value is stored as an on/off logical value of type `matlab.lang.OnOffSwitchState`.

- If you set this property to 'on', then the appearance of the EGT indicator indicates that the EGT indicator is operational.
- If you set this property to 'off', then the appearance of the EGT indicator appears dimmed, indicating that the EGT indicator is not operational.

Position**Position — Location and size of EGT indicator**

[100 100 120 120] (default) | [left bottom width height]

Location and size of the EGT indicator relative to the parent container, specified as the vector, [left bottom width height]. This table describes each element in the vector.

Element	Description
left	Distance from the inner left edge of the parent container to the outer left edge of an imaginary box surrounding the EGT indicator
bottom	Distance from the inner bottom edge of the parent container to the outer bottom edge of an imaginary box surrounding the EGT indicator
width	Distance between the right and left outer edges of the EGT indicator
height	Distance between the top and bottom outer edges of the EGT indicator

All measurements are in pixel units.

The **Position** values are relative to the drawable area of the parent container. The drawable area is the area inside the borders of the container and does not include the area occupied by decorations such as a menu bar or title.

Example: [200 120 120 120]

InnerPosition — Inner location and size of EGT indicator

[100 100 120 120] (default) | [left bottom width height]

Inner location and size of the EGT indicator, specified as [left bottom width height]. Position values are relative to the parent container. All measurements are in pixel units. This property value is identical to the **Position** property.

OuterPosition — Outer location and size of EGT indicator

[100 100 120 120] (default) | [left bottom width height]

This property is read-only.

Outer location and size of the EGT indicator returned as `[left bottom width height]`. Position values are relative to the parent container. All measurements are in pixel units. This property value is identical to the `Position` property.

Layout — Layout options

empty `LayoutOptions` array (default) | `GridLayoutOptions` object

Layout options, specified as a `GridLayoutOptions` object. This property specifies options for components that are children of grid layout containers. If the component is not a child of a grid layout container (for example, it is a child of a figure or panel), then this property is empty and has no effect. However, if the component is a child of a grid layout container, you can place the component in the desired row and column of the grid by setting the `Row` and `Column` properties on the `GridLayoutOptions` object.

For example, this code places an EGT indicator in the third row and second column of its parent grid.

```
g = ui([4 3]);
gauge = uiaeroegt(g);
gauge.Layout.Row = 3;
gauge.Layout.Column = 2;
```

To make the EGT indicator span multiple rows or columns, specify the `Row` or `Column` property as a two-element vector. For example, this EGT indicator spans columns 2 through 3:

```
gauge.Layout.Column = [2 3];
```

Callbacks

CreateFcn — Creation function

' ' (default) | function handle | cell array | character vector

Object creation function, specified as one of these values:

- Function handle.
- Cell array in which the first element is a function handle. Subsequent elements in the cell array are the arguments to pass to the callback function.
- Character vector containing a valid MATLAB expression (not recommended). MATLAB evaluates this expression in the base workspace.

For more information about specifying a callback as a function handle, cell array, or character vector, see “Write Callbacks in App Designer”.

This property specifies a callback function to execute when MATLAB creates the object. MATLAB initializes all property values before executing the `CreateFcn` callback. If you do not specify the `CreateFcn` property, then MATLAB executes a default creation function.

Setting the `CreateFcn` property on an existing component has no effect.

If you specify this property as a function handle or cell array, you can access the object that is being created using the first argument of the callback function. Otherwise, use the `gcbo` function to access the object.

DeleteFcn — Deletion function

' ' (default) | function handle | cell array | character vector

Object deletion function, specified as one of these values:

- Function handle.
- Cell array in which the first element is a function handle. Subsequent elements in the cell array are the arguments to pass to the callback function.
- Character vector containing a valid MATLAB expression (not recommended). MATLAB evaluates this expression in the base workspace.

For more information about specifying a callback as a function handle, cell array, or character vector, see “Write Callbacks in App Designer”.

This property specifies a callback function to execute when MATLAB deletes the object. MATLAB executes the `DeleteFcn` callback before destroying the properties of the object. If you do not specify the `DeleteFcn` property, then MATLAB executes a default deletion function.

If you specify this property as a function handle or cell array, you can access the object that is being deleted using the first argument of the callback function. Otherwise, use the `gcbo` function to access the object.

Callback Execution Control

Interruptible — Callback interruption

'on' (default) | on/off logical value

Callback interruption, specified as 'on' or 'off', or as numeric or logical 1 (true) or 0 (false). A value of 'on' is equivalent to `true`, and 'off' is equivalent to `false`. Thus, you can use the value of this property as a logical value. The value is stored as an on/off logical value of type `matlab.lang.OnOffSwitchState`.

This property determines if a running callback can be interrupted. There are two callback states to consider:

- The running callback is the currently executing callback.
- The interrupting callback is a callback that tries to interrupt the running callback.

Whenever MATLAB invokes a callback, that callback attempts to interrupt the running callback (if one exists). The `Interruptible` property of the object owning the running callback determines if interruption is allowed.

- A value of 'on' allows other callbacks to interrupt the object's callbacks. The interruption occurs at the next point where MATLAB processes the queue, such as when there is a `drawnow`, `figure`, `uifigure`, `getframe`, `waitfor`, or `pause` command.
 - If the running callback contains one of those commands, then MATLAB stops the execution of the callback at that point and executes the interrupting callback. MATLAB resumes executing the running callback when the interrupting callback completes.
 - If the running callback does not contain one of those commands, then MATLAB finishes executing the callback without interruption.
- A value of 'off' blocks all interruption attempts. The `BusyAction` property of the object owning the interrupting callback determines if the interrupting callback is discarded or put into a queue.

Note Callback interruption and execution behave differently in these situations:

- If the interrupting callback is a `DeleteFcn`, `CloseRequestFcn` or `SizeChangedFcn` callback, then the interruption occurs regardless of the `Interruptible` property value.

- If the running callback is currently executing the `waitfor` function, then the interruption occurs regardless of the `Interruptible` property value.
- Timer objects execute according to schedule regardless of the `Interruptible` property value.

When an interruption occurs, MATLAB does not save the state of properties or the display. For example, the object returned by the `gca` or `gcf` command might change when another callback executes.

BusyAction — Callback queuing

'queue' (default) | 'cancel'

Callback queuing, specified as 'queue' or 'cancel'. The `BusyAction` property determines how MATLAB handles the execution of interrupting callbacks. There are two callback states to consider:

- The running callback is the currently executing callback.
- The interrupting callback is a callback that tries to interrupt the running callback.

Whenever MATLAB invokes a callback, that callback attempts to interrupt a running callback. The `Interruptible` property of the object owning the running callback determines if interruption is permitted. If interruption is not permitted, then the `BusyAction` property of the object owning the interrupting callback determines if it is discarded or put in the queue. These are possible values of the `BusyAction` property:

- 'queue' — Puts the interrupting callback in a queue to be processed after the running callback finishes execution.
- 'cancel' — Does not execute the interrupting callback.

BeingDeleted — Deletion status

on/off logical value

This property is read-only.

Deletion status, returned as an on/off logical value of type `matlab.lang.OnOffSwitchState`.

MATLAB sets the `BeingDeleted` property to 'on' when the `DeleteFcn` callback begins execution. The `BeingDeleted` property remains set to 'on' until the component object no longer exists.

Check the value of the `BeingDeleted` property to verify that the object is not about to be deleted before querying or modifying it.

Parent/Child

Parent — Parent container

Figure object (default) | Panel object | Tab object | ButtonGroup object | GridLayout object

Parent container, specified as a Figure object created using the `uifigure` function, or one of its child containers: `Tab`, `Panel`, `ButtonGroup`, or `GridLayout`. If no container is specified, MATLAB calls the `uifigure` function to create a new Figure object that serves as the parent container.

HandleVisibility — Visibility of object handle

'on' (default) | 'callback' | 'off'

Visibility of the object handle, specified as 'on', 'callback', or 'off'.

This property controls the visibility of the object in its parent's list of children. When an object is not visible in its parent's list of children, it is not returned by functions that obtain objects by searching the object hierarchy or querying properties. These functions include `get`, `findobj`, `clf`, and `close`. Objects are valid even if they are not visible. If you can access an object, you can set and get its properties, and pass it to any function that operates on objects.

HandleVisibility Value	Description
'on'	The object is always visible.
'callback'	The object is visible from within callbacks or functions invoked by callbacks, but not from within functions invoked from the command line. This option blocks access to the object at the command-line, but allows callback functions to access it.
'off'	The object is invisible at all times. This option is useful for preventing unintended changes to the UI by another function. Set the <code>HandleVisibility</code> to 'off' to temporarily hide the object during the execution of that function.

Identifiers

Type — Type of graphics object

'uiaeroegt'

This property is read-only.

Type of graphics object, returned as 'uiaeroegt'.

Tag — Object identifier

' ' (default) | character vector | string scalar

Object identifier, specified as a character vector or string scalar. You can specify a unique `Tag` value to serve as an identifier for an object. When you need access to the object elsewhere in your code, you can use the `findobj` function to search for the object based on the `Tag` value.

UserData — User data

[] (default) | array

User data, specified as any MATLAB array. For example, you can specify a scalar, vector, matrix, cell array, character array, table, or structure. Use this property to store arbitrary data on an object.

If you are working in App Designer, create public or private properties in the app to share data instead of using the `UserData` property. For more information, see “Share Data Within App Designer Apps”.

See Also

uiaeroegt

Topics

“Create and Configure Flight Instrument Component and an Animation Object” on page 2-49

“Display Flight Trajectory Data Using Flight Instruments and Flight Animation” on page 5-111

Introduced in R2018b

fieldOfView

Package: satelliteScenario

Visualize field of view of conical sensor

Syntax

```
fieldOfView(sensor)
fieldOfView(sensor,Name,Value)
fov = fieldOfView(____)
```

Description

`fieldOfView(sensor)` adds a `FieldOfView` object to the specified conical sensor, and draws contours on the Earth. Each contour represents the field of view of a conical sensor in `sensor` based on the current state of the scenario.

Locations inside the contour are inside the field of view. If no viewer is open, a new viewer is launched, and the field of view contours are shown in the open viewer. If a viewer is already open, the field of view contours are added to it. The contours are the lines of intersection of the surface of the earth and the field of view cone. The half angle of the field of view cone is equal to the `MaxViewAngle` property of the conical sensor, and the axis of the cone is the `z`-axis (or boresight) of the conical sensor. The vertex of the cone is located at the position of the conical sensor. The cone becomes wider along the positive body `z`-axis of the conical sensor.

`fieldOfView(sensor,Name,Value)` specifies options by using one or more name-value arguments.

`fov = fieldOfView(____)` returns a vector of handles to the added field of view graphic objects. Specify any input combination from previous syntaxes.

Input Arguments

sensor — Conical sensor

`ConicalSensor` object

Conical sensor, specified as a `ConicalSensor` object.

Name-Value Pair Arguments

Specify optional comma-separated pairs of `Name,Value` arguments. `Name` is the argument name and `Value` is the corresponding value. `Name` must appear inside quotes. You can specify several name and value pair arguments in any order as `Name1,Value1,...,NameN,ValueN`.

Example: `'LineWidth',2.5` sets the line width of the field of view to 2.5 pixels.

LineWidth — Visual width of field of view contour

1 (default) | scalar in the range (0 10]

Visual width of the field of view contour in pixels, specified as a scalar in the range (0 10].

The line width cannot be thinner than the width of a pixel. If you set the line width to a value that is less than the width of a pixel on your system, the line displays as one pixel wide.

LineColor — Color of field of view contour


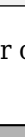
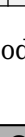
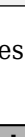
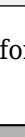
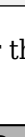
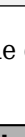

[0 1 0] (default) | RGB triplet | RGB triplet | string scalar of color name | character vector of color name

Color of field of view contour, specified as an RGB triplet, hexadecimal color code, a color name, or a short name.

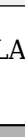
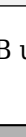
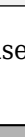
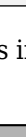
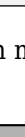
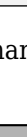
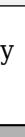
For a custom color, specify an RGB triplet or a hexadecimal color code.

- An RGB triplet is a three-element row vector whose elements specify the intensities of the red, green, and blue components of the color. The intensities must be in the range [0, 1]; for example, [0.4 0.6 0.7].
- A hexadecimal color code is a character vector or a string scalar that starts with a hash symbol (#) followed by three or six hexadecimal digits, which can range from 0 to F. The values are not case sensitive. Thus, the color codes '#FF8800', '#ff8800', '#F80', and '#f80' are equivalent.

Alternatively, you can specify some common colors by name. This table lists the named color options, the equivalent RGB triplets, and hexadecimal color codes.

Color Name	Short Name	RGB Triplet	Hexadecimal Color Code	Appearance
'red'	'r'	[1 0 0]	'#FF0000'	
'green'	'g'	[0 1 0]	'#00FF00'	
'blue'	'b'	[0 0 1]	'#0000FF'	
'cyan'	'c'	[0 1 1]	'#00FFFF'	
'magenta'	'm'	[1 0 1]	'#FF00FF'	
'yellow'	'y'	[1 1 0]	'#FFFF00'	
'black'	'k'	[0 0 0]	'#000000'	
'white'	'w'	[1 1 1]	'#FFFFFF'	
'none'	Not applicable	Not applicable	Not applicable	No color

Here are the RGB triplets and hexadecimal color codes for the default colors MATLAB uses in many types of plots.

RGB Triplet	Hexadecimal Color Code	Appearance
[0 0.4470 0.7410]	'#0072BD'	
[0.8500 0.3250 0.0980]	'#D95319'	
[0.9290 0.6940 0.1250]	'#EDB120'	
[0.4940 0.1840 0.5560]	'#7E2F8E'	
[0.4660 0.6740 0.1880]	'#77AC30'	
[0.3010 0.7450 0.9330]	'#4DBEEE'	
[0.6350 0.0780 0.1840]	'#A2142F'	

Example: 'blue'

Example: [0 0 1]

Example: '#0000FF'

Output Arguments

fov — Field of view of conical sensor

row vector of `FieldOfView` objects

Field of view of conical sensor, returned as a row vector of `FieldOfView` objects.

See Also

Objects

`satelliteScenario` | `satelliteScenarioViewer`

Functions

`access` | `conicalSensor` | `groundStation` | `hide` | `play` | `show`

Topics

“Satellite Scenario Key Concepts” on page 2-61

Introduced in R2021a

FieldOfView

Field of view object belonging to satellite scenario

Description

The FieldOfView object defines a field of view object belonging to a satellite scenario.

Creation

You can create a FieldOfView object using the fieldOfView object function of the ConicalSensor object.

Properties

LineWidth — Visual width of field of view contour

1 (default) | scalar in the range (0 10]

Visual width of the field of view contour in pixels, specified as a scalar in the range (0 10].

The line width cannot be thinner than the width of a pixel. If you set the line width to a value that is less than the width of a pixel on your system, the line displays as one pixel wide.

LineColor — Color of field of view contour


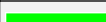

[0 1 0] (default) | RGB triplet | RGB triplet | string scalar of color name | character vector of color name






Color of field of view contour, specified as an RGB triplet, hexadecimal color code, a color name, or a short name.

For a custom color, specify an RGB triplet or a hexadecimal color code.





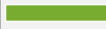
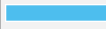

- An RGB triplet is a three-element row vector whose elements specify the intensities of the red, green, and blue components of the color. The intensities must be in the range [0, 1]; for example, [0.4 0.6 0.7].
- A hexadecimal color code is a character vector or a string scalar that starts with a hash symbol (#) followed by three or six hexadecimal digits, which can range from 0 to F. The values are not case sensitive. Thus, the color codes '#FF8800', '#ff8800', '#F80', and '#f80' are equivalent.

Alternatively, you can specify some common colors by name. This table lists the named color options, the equivalent RGB triplets, and hexadecimal color codes.

Color Name	Short Name	RGB Triplet	Hexadecimal Color Code	Appearance
'red'	'r'	[1 0 0]	'#FF0000'	
'green'	'g'	[0 1 0]	'#00FF00'	
'blue'	'b'	[0 0 1]	'#0000FF'	

Color Name	Short Name	RGB Triplet	Hexadecimal Color Code	Appearance
'cyan'	'c'	[0 1 1]	'#00FFFF'	
'magenta'	'm'	[1 0 1]	'#FF00FF'	
'yellow'	'y'	[1 1 0]	'#FFFF00'	
'black'	'k'	[0 0 0]	'#000000'	
'white'	'w'	[1 1 1]	'#FFFFFF'	
'none'	Not applicable	Not applicable	Not applicable	No color

Here are the RGB triplets and hexadecimal color codes for the default colors MATLAB uses in many types of plots.

RGB Triplet	Hexadecimal Color Code	Appearance
[0 0.4470 0.7410]	'#0072BD'	
[0.8500 0.3250 0.0980]	'#D95319'	
[0.9290 0.6940 0.1250]	'#EDB120'	
[0.4940 0.1840 0.5560]	'#7E2F8E'	
[0.4660 0.6740 0.1880]	'#77AC30'	
[0.3010 0.7450 0.9330]	'#4DBEEE'	
[0.6350 0.0780 0.1840]	'#A2142F'	

Example: 'blue'

Example: [0 0 1]

Example: '#0000FF'

VisibilityMode — Visibility mode of field of view contour

'inherit' (default) | 'manual'

Visibility mode of the field of view contour, specified as one of these values:

- 'inherit' — Visibility of the graphic matches that of the parent
- 'manual' — Visibility of the graphic is not inherited and is independent of that of the parent

Object Functions

show Show object in satellite scenario viewer

hide Hides satellite scenario entity from viewer

See Also

Objects

satelliteScenario | satelliteScenarioViewer

Functions

access | groundStation | hide | play | show

Topics

“Satellite Scenario Key Concepts” on page 2-61

Introduced in R2021a

fanimation (Aero.FlightGearAnimation)

Construct FlightGear animation object

Syntax

```
h = fanimation  
h = Aero.FlightGearAnimation
```

Description

`h = fanimation` and `h = Aero.FlightGearAnimation` construct a FlightGear animation object. The FlightGear animation object is returned to `h`.

Examples

Construct a FlightGear animation object, `h`:

```
h = fanimation
```

See Also

`Aero.FlightGearAnimation`

Introduced in R2007a

findstartstoptimes (Aero.Body)

Return start and stop times of time series data

Syntax

```
[tstart,tstop] = findstartstoptimes(h,tsdata)
[tstart,stop] = h.findstartstoptimes(tsdata)
```

Description

[tstart,tstop] = findstartstoptimes(h,tsdata) and [tstart,stop] = h.findstartstoptimes(tsdata) return the start and stop times of time series data tsdata for the animation body object h.

Examples

Find the start and stop times of the time series data, *tsdata*.

```
b=Aero.Body;
b.load('pa24-250_orange.ac','Ac3d');
tsdata = [ ...
    0, 1,1,1, 0,0,0; ...
    10 2,2,2, 1,1,1; ];
b.TimeSeriesSource = tsdata;
[tstart,tstop] = findstartstoptimes(b,tsdata);
```

See Also

load

Introduced in R2007a

findstartstoptimes (Aero.Node)

Return start and stop times for time series data

Syntax

```
[tstart,tstop] = findstartstoptimes(h,tsdata)
[tstart,stop] = h.findstartstoptimes(tsdata)
```

Description

[tstart,tstop] = findstartstoptimes(h,tsdata) and [tstart,stop] = h.findstartstoptimes(tsdata) return the start and stop times of time series data tsdata for the virtual reality animation object h.

Examples

Find the start and stop times of the time series data, takeoffData.

```
h = Aero.VirtualRealityAnimation;
h.VRWorldFilename = [matlabroot,'/toolbox/aero/astdemos/asttkoff.wrl'];
copyfile(h.VRWorldFilename,[tempdir,'asttkoff.wrl'],'f');
h.VRWorldFilename = [tempdir,'asttkoff.wrl'];
h.initialize();
load takeoffData;
h.Nodes{7}.TimeseriesSource = takeoffData;
h.Nodes{7}.TimeseriesSourceType = 'StructureWith Time';
[tstart,stop]=h.Nodes{7}.findstartstoptimes;
```

Introduced in R2007b

flat2lla

Convert from flat Earth position to array of geodetic coordinates

Syntax

```
lla = flat2lla(flathearth_pos, llo, psio, href)
lla = flat2lla(____, ellipsoidModel)
lla = flat2lla(____, flattening, equatorialRadius)
```

Description

`lla = flat2lla(flathearth_pos, llo, psio, href)` estimates an array of geodetic coordinates, `lla`, from an array of flat Earth coordinates, `flathearth_pos`. This function estimates the `lla` value with respect to a reference location that you define with `llo`, `psio`, and `href`.

`lla = flat2lla(____, ellipsoidModel)` estimates the coordinates for a specific ellipsoid planet.

`lla = flat2lla(____, flattening, equatorialRadius)` estimates the coordinates for a custom ellipsoid planet defined by `flattening` and `equatorialRadius`.

Examples

Estimate Latitude, Longitude, and Altitude at Single Coordinate

Estimate latitude, longitude, and altitude at a single coordinate:

```
lla = flat2lla( [ 4731 4511 120 ], [0 45], 5, -100)

lla =
    0.0391    45.0441   -20.0000
```

Estimate Latitudes, Longitudes, and Altitudes at Multiple Coordinates with WGS84 Ellipsoid Model

Estimate latitudes, longitudes, and altitudes at multiple coordinates with the WGS84 ellipsoid model:

```
lla = flat2lla( [ 4731 4511 120; 0 5074 4498 ], [0 45], 5, -100, 'WGS84' )

lla =
    1.0e+03 *
    0.0000    0.0450   -0.0200
   -0.0000    0.0450   -4.3980
```

Estimate Latitudes, Longitudes, and Altitudes at Multiple Coordinates with Custom Ellipsoid Model:

Estimate latitudes, longitudes, and altitudes at multiple coordinates with a custom ellipsoid model:

```
f = 1/196.877360;
Re = 3397000;
lla = flat2lla( [ 4731 4511 120; 0 5074 4498 ], [ 0 45], 5, -100, f, Re )

lla =
    1.0e+03 *

    0.0001    0.0451   -0.0200
   -0.0000    0.0451   -4.3980
```

Input Arguments

flatearth_pos — Flat Earth position coordinates

3-element vector

Flat Earth position coordinates, specified as 3-element vector, in meters.

Data Types: double

llo — Latitude and longitude of reference location

m-by-2 array

Latitude and longitude of reference location, specified as an *m*-by-2 array in degrees, for the origin of the estimation and the origin of the flat Earth coordinate system.

Data Types: double

psio — Angular direction of flat Earth

scalar

Angular direction of flat Earth *x*-axis, specified as a scalar. The angular direction is the degrees clockwise from the north, which is the angle in degrees used for converting flat Earth *x* and *y* coordinates to the north and east coordinates.

Data Types: double

href — Reference height

scalar

Reference height from the surface of the Earth to the flat Earth frame with respect to the flat Earth frame, specified as a scalar, in meters.

Data Types: double

ellipsoidModel — Ellipsoid planet model

'WGS84' (default)

Ellipsoid planet model. 'WGS84' is the only option.

Data Types: char | string

flattening — Flattening of planet

1/298.257223563 (default) | scalar

Flattening of the planet, specified as a double scalar.

Data Types: double

equatorialRadius – Planetary equatorial radius

scalar

Planetary equatorial radius, specified as a scalar, in meters.

Data Types: double

Output Arguments

11a – Geodetic coordinates

m-by-3 array

Geodetic coordinates (latitude, longitude, and altitude), returned as an *m*-by-3 array, in [degrees, degrees, meters].

Algorithms

The estimation begins by transforming the flat Earth *x* and *y* coordinates to north and east coordinates. The transformation has the form of

$$\begin{bmatrix} N \\ E \end{bmatrix} = \begin{bmatrix} \cos\psi & -\sin\psi \\ \sin\psi & \cos\psi \end{bmatrix} \begin{bmatrix} p_x \\ p_y \end{bmatrix},$$

where($\bar{\psi}$) is the angle in degrees clockwise between the *x*-axis and north.

To convert the north and east coordinates to geodetic latitude and longitude, the estimation uses the radius of the curvature in the prime vertical (R_N) and the radius of the curvature in the meridian (R_M). (R_N) and (R_M) are defined by the following relationships:

$$R_N = \frac{R}{\sqrt{1 - (2f - f^2)\sin^2\mu_0}},$$

and

$$R_M = R_N \frac{1 - (2f - f^2)}{1 - (2f - f^2)\sin^2\mu_0},$$

where (R) is the equatorial radius of the planet and(\bar{f}) is the flattening of the planet.

Small changes in the latitude and longitude are approximated from small changes in the North and East positions by

$$d\mu = \text{atan}\left(\frac{1}{R_M}\right)dN$$

$$d\iota = \text{atan}\left(\frac{1}{R_N \cos\mu}\right)dE$$

and

$$d\iota = \operatorname{atan}\left(\frac{1}{R_N \cos\mu}\right) dE.$$

The output latitude and longitude are the initial latitude and longitude plus the small changes in latitude and longitude.

$$\mu = \mu_0 + d\mu$$

$$\iota = \iota_0 + d\iota$$

The altitude is the negative flat Earth z -axis value minus the reference height (h_{ref}).

$$h = -p_z - h_{ref}$$

References

- [1] Etkin, B., *Dynamics of Atmospheric Flight*. New York: John Wiley & Sons, 1972.
- [2] Stevens, B. L., and F. L. Lewis, *Aircraft Control and Simulation*, 2nd ed. New York: John Wiley & Sons, 2003.

See Also

lla2flat

Introduced in R2011a

flowfanno

Fanno line flow relations

Syntax

```
[mach, T, P, rho, velocity, P0, fanno] = flowfanno(gamma, fanno_flow, mtype)
```

Description

[*mach*, *T*, *P*, *rho*, *velocity*, *P0*, *fanno*] = flowfanno(*gamma*, *fanno_flow*, *mtype*) returns an array for each Fanno line flow relation. This function calculates the arrays for a given set of specific heat ratios (*gamma*), and any one of the Fanno flow types. You select the Fanno flow type with *mtype*.

This function uses Fanno variables given by the following. *F* is the Fanno parameter given by $F = fL/D$. *f* is the friction coefficient. *L* is the length of constant area duct required to achieve sonic flow. *D* is the hydraulic diameter of the duct.

This function assumes that variables vary in one dimension only. It also assumes that the main mechanism for the change of flow variables is the change of cross-sectional area of the flow stream tubes.

If the temperature experiences large fluctuations, the perfect gas assumption might be invalid. If the stagnation temperature is above 1500 K, do not assume constant specific heats. In this case, the medium ceases to be a calorically perfect gas. Consider it a thermally perfect gas. See 2 for thermally perfect gas correction factors. If the temperature is so high that molecules dissociate and ionize (static temperature 5000 K for air), you cannot assume a perfect gas.

Input Arguments

gamma

Array of *N* specific heat ratios. *gamma* must be either a scalar or an array of *N* real numbers greater than 1. *gamma* must be a real, finite scalar greater than 1 for the following input modes: subsonic total pressure ratio, supersonic total pressure ratio, subsonic Fanno parameter, and supersonic Fanno parameter.

fanno_flow

Array of real numerical values for one Fanno flow. This argument can be one of the following:

- Array of Mach numbers. *flow_fanno* must be a scalar or an array of *N* real numbers greater than or equal to 0. If *flow_fanno* and *gamma* are arrays, they must be the same size.

Use *flow_fanno* with the *mtype* value 'mach'. Because 'mach' is the default of *mtype*, *mtype* is optional when this array is the input mode.

- Array of temperature ratios. The temperature ratio is the local static temperature over the reference static temperature for sonic flow. This array must be a scalar or array of *N* real numbers:

- Greater than or equal to 0 (as the Mach number approaches infinity)
- Less than or equal to $(\gamma+1)/2$ (at Mach number equal 0)

Use *flow_fanno* with *mtype* value 'temp'.

- Array of pressure ratios. The pressure ratio is the local static pressure over the reference static pressure for sonic flow. *flow_fanno* must be a scalar or array of real numbers greater than or equal to 0. If *flow_fanno* and *gamma* are arrays, they must be the same size.

Use *flow_fanno* with *mtype* value 'pres'.

- Array of density ratios. The density ratio is the local density over the reference density for sonic flow. *flow_fanno* must be a scalar or array of real numbers. These numbers must be greater than or equal to:

$\sqrt{(\gamma-1)/(\gamma+1)}$ (as the Mach number approaches infinity).

If *flow_fanno* and *gamma* are arrays, they must be the same size.

Use *flow_fanno* with *mtype* value 'dens'.

- Array of velocity ratios. The velocity ratio is the local velocity over the reference velocity for sonic flow. *flow_fanno* must be a scalar or an array of *N* of real numbers:

- Greater than or equal to 0
- Less than or equal to $\sqrt{(\gamma+1)/(\gamma-1)}$ (as the Mach number approaches infinity)

If *flow_fanno* and *gamma* are both arrays, they must be the same size.

Use *flow_fanno* with *mtype* value 'velo'.

- Scalar value of total pressure ratio. The total pressure ratio is the local total pressure over the reference total pressure for sonic flow. *flow_fanno* must be greater than or equal to 1.

Use *flow_fanno* with *mtype* values 'totalp' and 'totalpsup'.

- Scalar value for Fanno parameter. The Fanno parameter is $\text{flow_fanno} = fL/D$. *f* is the friction coefficient. *L* is the length of constant area duct required to achieve sonic flow. *D* is the hydraulic diameter of the duct. In subsonic mode, *flow_fanno* must be greater than or equal to 0. In supersonic mode, *flow_fanno* must be:

- Greater than or equal to 0 (at Mach number equal 1)
- Less than or equal to $(\gamma+1)/(2*\gamma)*\log((\gamma+1)/(\gamma-1))-1/\gamma$ (as Mach number approaches infinity)

Use *flow_fanno* with *mtype* values 'fannosub' and 'fannosup'.

mtype

Input mode for the type of Fanno flow in *fanno_flow*.

Type	Description
'mach'	Default Mach number
'temp'	Temperature ratio
'pres'	Pressure ratio

Type	Description
'dens '	Density ratio
'velo '	Velocity ratio
'totalpsub '	Subsonic total pressure ratio
'totalpsup '	Supersonic total pressure ratio
'fannosub '	Subsonic Fanno parameter
'fannosup '	Supersonic Fanno parameter

Output Arguments

All outputs are the same size as the array inputs. If there are no array inputs, all outputs are scalars.

mach

Array of Mach numbers.

T

Array of temperature ratios. The temperature ratio is the local static temperature over the reference static temperature for sonic flow.

P

Array of pressure ratios. The pressure ratio is the local static pressure over the reference static pressure for sonic flow.

rho

Array of density ratio. The density ratio is the local density over the reference density for sonic flow.

velocity

Array of velocity ratios. The velocity ratio is the local velocity over the reference velocity for sonic flow.

P0

Array of stagnation (total) pressure ratio. The total pressure ratio is the local total pressure over the reference total pressure for sonic flow.

fanno

Array of Fanno parameters. The Fanno parameter is $F = fL/D$. f is the friction coefficient. L is the length of constant area duct required to achieve sonic flow. D is the hydraulic diameter of the duct.

Examples

Calculate the Fanno line flow relations for air ($\gamma = 1.4$) for subsonic Fanno parameter 1.2. The following returns scalar values for *mach*, *T*, *P*, *rho*, *velocity*, *P0*, and *fanno*.

```
[mach, T, P, rho, velocity, P0, fanno] = flowfanno(1.4, 1.2, 'fannosub')
```

Calculate the Fanno line flow relations for gases with specific heat ratios given in the following 1 x 4 row array for the Mach number 0.5. The following yields a 1 x 4 row array for *mach*, *T*, *P*, *rho*, *velocity*, *P0*, and *fanno*.

```
gamma = [1.3, 1.33, 1.4, 1.67];  
[mach, T, P, rho, velocity, P0, fanno] = flowfanno(gamma, 0.5)
```

Calculate the Fanno line flow relations for a specific heat ratio of 1.4 and range of temperature ratios from 0.40 to 0.70 in increments of 0.10. The following returns a 4 x 1 column array for *mach*, *T*, *P*, *rho*, *velocity*, *P0*, and *fanno*.

```
[mach, T, P, rho, velocity, P0, fanno] = flowfanno(1.4, [1.1 1.2], 'temp')
```

Calculate the Fanno line flow relations for gases with specific heat ratio and velocity ratio combinations as shown. The following returns a 1 x 2 array for *mach*, *T*, *P*, *rho*, *velocity*, *P0*, and *fanno* each. The elements of each array correspond to the inputs element-wise.

```
gamma = [1.3, 1.4];  
V = [0.53, 0.49];  
[MACH, T, P, RHO, V, P0, F] = flowfanno(gamma, V, 'velo')
```

References

1. James, J. E. A., *Gas Dynamics, Second Edition*, Allyn and Bacon, Inc, Boston, 1984.
2. *NACA Technical Report 1135*, 1953, National Advisory Committee on Aeronautics, Ames Research Staff, Moffett Field, Calif. Pages 667-671.

See Also

[flowisentropic](#) | [flownormalshock](#) | [flowprandtlmeyer](#) | [flowrayleigh](#)

Introduced in R2010a

flowisentropic

Isentropic flow ratios

Syntax

```
[mach, T, P, rho, area] = flowisentropic(gamma, flow, mtype)
```

Description

[*mach*, *T*, *P*, *rho*, *area*] = flowisentropic(*gamma*, *flow*, *mtype*) returns an array. This array contains an isentropic flow Mach number (*mach*), temperature ratio (*T*), pressure ratio (*P*), density ratio (*rho*), and area ratio (*area*). This function calculates these arrays given a set of specific heat ratios (*gamma*), and any one of the isentropic flow types. You select the isentropic flow with *mtype*.

This function assumes that variables vary in one dimension only. It also assumes that the main mechanism for the change of flow variables is the change of cross-sectional area of the flow stream tubes.

This function assumes that the environment is a perfect gas. In the following instances, the function cannot assume a perfect gas environment. If there is a large change in either temperature or pressure without a proportionally large change in the other, the function cannot assume a perfect gas environment. . If the stagnation temperature is above 1500 K, do not assume that constant specific heats. In this case, the medium ceases to be a calorically perfect gas. Consider it a thermally perfect gas. See 2 for thermally perfect gas correction factors. If the temperature is so high that molecules dissociate and ionize (static temperature 5000 K for air), you cannot assume a calorically or thermally perfect gas.

Input Arguments

gamma

Array of *N* specific heat ratios. *gamma* must be a scalar or array of *N* real numbers greater than 1. For subsonic area ratio input mode and supersonic area ratio input mode, *gamma* must be a real, finite scalar greater than 1.

flow

Array of real numerical values for one of the isentropic flow relations. This argument can be one of the following:

- Array of Mach numbers. *flow* must be a scalar or an array of *N* real numbers greater than or equal to 0. If *flow* and *gamma* are arrays, they must be the same size.

Use *flow* with the *mtype* value 'mach'. Because 'mach' is the default of *mtype*, *mtype* is optional when this array is the input mode.

- Array of temperature ratios. The temperature ratio is the local static temperature over the stagnation temperature. *flow* must be a scalar or an array of real numbers:

- Greater than or equal to 0 (as the Mach number approaches infinity)
- Less than or equal to 1 (at Mach number equal 0)

If *flow* and *gamma* are both arrays, they must be the same size.

Use *flow* with *mtype* value '*temp*'.

- Array of pressure ratios. The pressure ratio is the local static pressure over the stagnation pressure. *flow* must be a scalar or an array of real numbers:
 - Greater than or equal to 0 (as the Mach number approaches infinity)
 - Less than or equal to 1 (at Mach number equal 0)

If *flow* and *gamma* are both arrays, they must be the same size.

Use *flow* with *mtype* value '*pres*'.

- Array of density ratios. The density ratio is the local density over the stagnation density. *flow* must be a scalar or an array of real numbers:
 - Greater than or equal to 0 (as the Mach number approaches infinity)
 - Less than or equal to 1 (at Mach number equal 0)

If *flow* and *gamma* are both arrays, they must be the same size.

Use *flow* with *mtype* value '*dens*'.

- Scalar value of area ratio. *flow* must be a real value greater than or equal to 1.

Use *flow* with *mtype* value '*sup*'.

mtype

Input mode for the isentropic flow in *flow*.

Type	Description
'mach'	Default. Mach number.
'temp'	Temperature ratio.
'pres'	Pressure ratio.
'dens'	Density ratio.
'sub'	Subsonic area ratio. The subsonic area ratio is the local subsonic stream tube area over the reference stream tube area for sonic conditions.
'sup'	Supersonic area ratio. The supersonic area ratio is the local supersonic stream tube area over the reference stream tube area for sonic conditions.

Output Arguments

All outputs are the same size as the array inputs. If there are no array inputs, all outputs are scalars.

mach

Array of Mach numbers.

T

Array of temperature ratios. The temperature ratio is the local static temperature over the stagnation temperature.

P

Array of pressure ratios. The pressure ratio is the local static pressure over the stagnation pressure.

rho

Array of density ratios. The density ratio is the local density over the stagnation density.

area

Array of area ratios. The area ratio is the local stream tube area over the reference stream tube area for sonic conditions.

Examples

Calculate the isentropic flow relations for air ($\gamma = 1.4$) for a design subsonic area ratio of 1.255. This example returns scalar values for *mach*, *T*, *P*, *rho*, and *area*.

```
[mach, T, P, rho, area] = flowisentropic(1.4, 1.255, 'sub')
```

Calculate the isentropic flow relations for gases with specific heat ratios given in the following 1 x 4 row array for the Mach number 0.5. This example following returns a 1 x 4 row array for *mach*, *T*, *P*, *rho*, and *area*.

```
gamma = [1.3, 1.33, 1.4, 1.67];
[mach, T, P, rho, area] = flowisentropic(gamma, 0.5)
```

Calculate the isentropic flow relations for a specific heat ratio of 1.4. Also calculate range of temperature ratios from 0.40 to 0.70 in increments of 0.10. This example returns a 4 x 1 column array for *mach*, *T*, *P*, *rho*, and *area*.

```
[mach, T, P, rho, area] = flowisentropic(1.4, (0.40:0.10:0.70)', 'temp')
```

Calculate the isentropic flow relations for gases with provided specific heat ratio and density ratio combinations. This example returns a 1 x 2 array for *mach*, *T*, *P*, *rho*, and *area* each. The elements of each vector correspond to the inputs element-wise.

```
gamma = [1.3, 1.4];
rho = [0.13, 0.9];
[mach, T, P, rho, area] = flowisentropic(gamma, rho, 'dens')
```

References

1. James, J. E. A., *Gas Dynamics, Second Edition*, Allyn and Bacon, Inc, Boston, 1984.
2. *NACA Technical Report 1135*, 1953, National Advisory Committee on Aeronautics, Ames Research Staff, Moffett Field, Calif. Pages 667-671.

See Also

[flowfanno](#) | [flownormalshock](#) | [flowprandtlmeyer](#) | [flowrayleigh](#)

Introduced in R2010a

flownormalshock

Normal shock relations

Syntax

```
[mach, T, P, rho, downstream_mach, P0, P1] = flownormalshock(gamma,
normal_shock_relations, mtype)
```

Description

[*mach*, *T*, *P*, *rho*, *downstream_mach*, *P0*, *P1*] = flownormalshock(*gamma*, *normal_shock_relations*, *mtype*) produces an array for each normal shock relation (*normal_shock_relations*). This function calculates these arrays for a given set of specific heat ratios (*gamma*) and any one of the normal shock relations (*normal_shock_relations*). *mtype* selects the normal shock relations that *normal_shock_relations* represents. All ratios are downstream value over upstream value. Consider upstream to be before or ahead of the shock; downstream is after or behind the shock.

This function assumes that the medium is a calorically perfect gas. It assumes that the flow is frictionless and adiabatic. It assumes that the flow variables vary in one dimension only. It assumes that the main mechanism for the change of flow variables is the change of cross-sectional area of the flow stream tubes.

If the temperature experiences large fluctuations, the perfect gas assumption might be invalid. If the stagnation temperature is above 1500 K, do not assume constant specific heats. In this case, the medium ceases to be a calorically perfect gas. You must then consider it a thermally perfect gas. See 2 for thermally perfect gas correction factors. If the temperature is so high that molecules dissociate and ionize (static temperature 5000 K for air), you cannot assume a perfect gas.

Input Arguments

gamma

Array of *N* specific heat ratios. *gamma* must be either a scalar or an array of *N* real numbers greater than 1. For temperature ratio, total pressure ratio, and Rayleigh-Pitot ratio input modes, *gamma* must be a real, finite scalar greater than 1.

normal_shock_relations

Array of real numerical values for one of the normal shock relations. This argument can be one of the following:

- Array of upstream Mach numbers. This array must be a scalar or an array of *N* real numbers greater than or equal to 1. If *normal_shock_relations* and *gamma* are arrays, they must be the same size.

Use *normal_shock_relations* with *mtype* value 'mach'. Because 'mach' is the default of *mtype*, *mtype* is optional when this array is the input mode.

- Scalar value of temperature ratio. The temperature ratio is the static temperature downstream of the shock over the static temperature upstream of the shock. *normal_shock_relations* must be a real scalar greater than or equal to 1.

Use *normal_shock_relations* with *mtype* value 'temp'.

- Array of pressure ratios. The pressure ratio is the static pressure downstream of the shock over the static pressure upstream of the shock. *normal_shock_relations* must be a scalar or array of real numbers greater than or equal to 1. If *normal_shock_relations* and *gamma* are arrays, they must be the same size.

Use *normal_shock_relations* with *mtype* value 'pres'.

- Array of density ratios. The density ratio is the density of the fluid downstream of the shock over the density upstream of the shock. *normal_shock_relations* must be a scalar or array of real numbers:

- Greater than or equal to 1 (at Mach number equal 1)
- Less than or equal to $(\gamma+1)/(\gamma-1)$ (as the Mach number approaches infinity)

If *normal_shock_relations* and *gamma* are arrays, they must be the same size. Use *normal_shock_relations* with *mtype* value 'dens'.

- Array of downstream Mach numbers. *normal_shock_relations* must be scalar or array of real numbers:

- Greater than or equal to 0 (as the Mach number approaches infinity)
- Less than or equal to $\sqrt{(\gamma-1)/(2*\gamma)}$ (at Mach number equal 1)

If *normal_shock_relations* and *gamma* are arrays, they must be the same size. Use *normal_shock_relations* with *mtype* value 'down'.

- Scalar value of total pressure ratio. The total pressure ratio is the total pressure downstream of the shock over the total pressure upstream of the shock. *normal_shock_relations* must be:

- Greater than or equal to 0 (as the Mach number approaches infinity)
- Less than or equal to 1 (at Mach number equal 1)

If *normal_shock_relations* and *gamma* are both arrays, they must be the same size. Use *normal_shock_relations* with *mtype* value 'totalp'.

- Scalar value of Rayleigh-Pitot ratio. The Rayleigh-Pitot ratio is the static pressure upstream of the shock over the total pressure downstream of the shock. *normal_shock_relations* must be:

- Real scalar greater than or equal to 0 (as the Mach number approaches infinity)
- Less than or equal to $((\gamma+1)/2)^{-\gamma/(\gamma-1)}$ (at Mach number equal 1)

If *normal_shock_relations* and *gamma* are both arrays, they must be the same size. Use *normal_shock_relations* with *mtype* value 'pito'.

mtype

Input mode for the normal shock relations in *normal_shock_relations*, specified as a character vector or string.

Type	Description
'mach'	Default. Mach number.
'temp'	Temperature ratio.
'pres'	Pressure ratio.
'dens'	Density ratio.
'down'	Downstream Mach number.
'totalp'	Total pressure ratio.
'pito'	Rayleigh-Pitot ratio.

Output Arguments

mach

Array of upstream Mach numbers.

P

Array of pressure ratios. The pressure ratio is the static pressure downstream of the shock over the static pressure upstream of the shock.

T

Array of temperature ratios. The temperature ratio is the static temperature downstream of the shock over the static temperature upstream of the shock.

rho

Array of density ratios. The density ratio is the density of the fluid downstream of the shock over the density upstream of the shock.

downstream_mach

Array of downstream Mach numbers.

P0

Array of total pressure ratios. The total pressure ratio is the total pressure downstream of the shock over the total pressure upstream of the shock.

P1

Array of Rayleigh-Pitot ratios. The Rayleigh-Pitot ratio is the static pressure upstream of the shock over the total pressure downstream of the shock.

Examples

Calculate the normal shock relations for air ($\gamma = 1.4$) for total pressure ratio of 0.61. The following returns scalar values for *mach*, *T*, *P*, *rho*, *downstream_mach*, *P0*, and *P1*.

```
[mach, T, P, rho, downstream_mach, P0, P1] = flownormalshock(1.4, 0.61, 'totalp')
```

Calculate the normal shock relations for gases with specific heat ratios given in the following 1 x 4 row array for upstream Mach number 1.5. The follow yields a 1 x 4 array for *mach*, *T*, *P*, *rho*, *downstream_mach*, *P0*, and *P1*.

```
gamma = [1.3, 1.33, 1.4, 1.67];  
[mach, T, P, rho, downstream_mach, P0, P1] = flownormalshock(gamma, 1.5)
```

Calculate the normal shock relations for a specific heat ratio of 1.4 and range of density ratios from 2.40 to 2.70 in increments of 0.10. The following returns a 4 x 1 column array for *mach*, *T*, *P*, *rho*, *downstream_mach*, *P0*, and *P1*.

```
[mach, T, P, rho, downstream_mach, P0, P1] = flownormalshock(1.4,...  
(2.4:.1:2.7)', 'dens')
```

Calculate the normal shock relations for gases with specific heat ratio and downstream Mach number combinations as shown. The following example returns a 1 x 2 array for *mach*, *T*, *P*, *rho*, *downstream_mach*, *P0*, and *P1* each, where the elements of each vector corresponds to the inputs element-wise.

```
gamma = [1.3, 1.4];  
downstream_mach = [.34, .49];  
[mach, T, P, rho, downstream_mach, P0, P1] = flownormalshock(gamma,...  
downstream_mach, 'down')
```

References

1. James, J. E. A., *Gas Dynamics, Second Edition*, Allyn and Bacon, Inc, Boston, 1984.
2. *NACA Technical Report 1135*, 1953, National Advisory Committee on Aeronautics, Ames Research Staff, Moffett Field, Calif. Pages 667-671.

See Also

[flowfanno](#) | [flowisentropic](#) | [flowprandtlmeyer](#) | [flowrayleigh](#)

Introduced in R2010a

flowprandtlmeyer

Calculate Prandtl-Meyer functions for expansion waves

Syntax

```
[mach, nu, mu] = flowprandtlmeyer(gamma, prandtlmeyer_array, mtype)
```

Description

[*mach*, *nu*, *mu*] = flowprandtlmeyer(*gamma*, *prandtlmeyer_array*, *mtype*) calculates the following: array of Mach numbers, *mach*, Prandtl-Meyer angles (*nu* in degrees) and Mach angles (*mu* in degrees). flowprandtlmeyer calculates these arrays for a given set of specific heat ratios, *gamma*, and any one of the Prandtl-Meyer types. You select the Prandtl-Meyer type with *mtype*.

The function assumes that the flow is two-dimensional. The function also assumes a smooth and gradual change in flow properties through the expansion fan.

Note, this function assumes that the environment is a perfect gas. In the following instances, it cannot assume a perfect gas environment. If there is a large change in either temperature or pressure without a proportionally large change in the other, it cannot assume a perfect gas environment. If the stagnation temperature is above 1500 K, the function cannot assume constant specific heats. In this case, you must consider it a thermally perfect gas. See 2 for thermally perfect gas correction factors. The local static temperature might be so high that molecules dissociate and ionize (static temperature 5000 K for air). In this case, you cannot assume a calorically or thermally perfect gas.

Input Arguments

gamma

Array of *N* specific heat ratios. *gamma* must be a scalar or array of *N* real numbers greater than 1. For subsonic area ratio input mode and supersonic area ratio input mode, *gamma* must be a real, finite scalar greater than 1.

prandtlmeyer_array

Array of real numerical values for one of the Prandtl-Meyer types. This argument can be one of the following:

- Array of Mach numbers. This array must be a scalar or an array of *N* real numbers greater than or equal to 0. If *prandtlmeyer_array* and *gamma* are arrays, they must be the same size.

Use *prandtlmeyer_array* with *mtype* value 'mach'. Note, because 'mach' is the default of *mtype*, *mtype* is optional when this array is the input mode.

- Scalar value for Prandtl-Meyer angle in degrees. This value is the angle change required for a Mach 1 flow to achieve a given Mach number after expansion. *prandtlmeyer_array* must be:
 - Real scalar greater than or equal to 0 (at Mach number equal 1)
 - Less than or equal to $90 * (\sqrt{(\gamma+1)/(\gamma-1)} - 1)$ (as the Mach number approaches infinity).

Use `prandtlmeyer_array` with `mtype` value 'nu'.

- Array of Mach angles in degrees. These values are the angles between the flow direction and the lines of pressure disturbance caused by supersonic motion. The Mach angle is a function of Mach number only. `prandtlmeyer_array` must be a scalar or array of N real numbers that are:
 - Greater than or equal to 0 (as the Mach number approaches infinity).
 - Less than or equal to 90 (at Mach number equal 1).

Use `prandtlmeyer_array` with `mtype` value 'mu'.

mtype

Isentropic flow variable represented by `prandtlmeyer_array`.

Type	Description
'mach'	Default. Mach number..
'nu'	Prandtl-Meyer angle
'mu'	Mach angle.

Output Arguments

mach

Array of Mach numbers. In Prandtl-Meyer angle input mode, `mach` outputs are the same size as the array input or array inputs. If there are no array inputs, `mach` is a scalar.

nu

Array of Prandtl-Meyer angles. The Prandtl-Meyer angle is the angle change required for a Mach 1 flow to achieve a given Mach number after expansion.

mu

Array of Mach angles. The Mach angle is between the flow direction and the lines of pressure disturbance caused by supersonic motion.

Examples

Calculate the Prandtl-Meyer relations for air ($\gamma = 1.4$) for Prandtl-Meyer angle 61 degrees. The following returns a scalar for `mach`, `nu`, and `mu`.

```
[mach, nu, mu] = flowprandtlmeyer(1.4, 61, 'nu')
```

Calculate the Prandtl-Meyer functions for gases with specific heat ratios. The following yields a 1 x 4 array for `nu`, but only a scalar for `mach` and `mu`.

```
gamma = [1.3, 1.33, 1.4, 1.67];
[mach, nu, mu] = flowprandtlmeyer(gamma, 1.5)
```

Calculate the Prandtl-Meyer angles for a specific heat ratio of 1.4 and range of Mach angles from 40 degrees to 70 degrees. This example uses increments of 10 degrees. The following returns a 4 x 1 column array for `mach`, `nu`, and `mu`.

```
[mach, nu, mu] = flowprandtlmeyer(1.4, (40:10:70)', 'mu')
```

Calculate the Prandtl-Meyer relations for gases with specific heat ratio and Mach number combinations as shown. The following returns a 1 x 2 array for nu and mu each, where the elements of each vector correspond to the inputs element-wise.

```
gamma = [1.3, 1.4];  
prandtlmeyer_array = [1.13, 9];  
[mach, nu, mu] = flowprandtlmeyer(gamma,prandtlmeyer_array)
```

References

1. James, J. E. A., *Gas Dynamics, Second Edition*, Allyn and Bacon, Inc, Boston, 1984.
2. *NACA Technical Report 1135*, 1953, National Advisory Committee on Aeronautics, Ames Research Staff, Moffett Field, Calif. Pages 667-671.

See Also

[flowfanno](#) | [flowisentropic](#) | [flownormalshock](#) | [flowrayleigh](#)

Introduced in R2010a

flowrayleigh

Rayleigh line flow relations

Syntax

```
[mach, T, P, rho, velocity, T0, P0] = flowrayleigh(gamma, rayleigh_flow, mtype)
```

Description

[*mach*, *T*, *P*, *rho*, *velocity*, *T0*, *P0*] = flowrayleigh(*gamma*, *rayleigh_flow*, *mtype*) returns an array for each Rayleigh line flow relation. This function calculates these arrays for a given set of specific heat ratios (*gamma*), and any one of the Rayleigh line flow types. You select the Rayleigh flow type with *mtype*.

This function assumes that the medium is a calorically perfect gas in a constant area duct. It assumes that the flow is steady, frictionless, and one dimensional. It also assumes that the main mechanism for the change of flow variables is heat transfer.

This function assumes that the environment is a perfect gas. In the following instances, it cannot assume a perfect gas environment. If there is a large change in either temperature or pressure without a proportionally large change in the other, it cannot assume a perfect gas environment. If the stagnation temperature is above 1500 K, do not assume constant specific heats. In this case, the medium ceases to be a calorically perfect gas; you must then consider it a thermally perfect gas. See 2 for thermally perfect gas correction factors. The local static temperature might be so high that molecules dissociate and ionize (static temperature 5000 K for air). In this case, you cannot assume a calorically or thermally perfect gas.

Input Arguments

gamma

Array of *N* specific heat ratios. *gamma* must be either a scalar or an array of *N* real numbers greater than 1. *gamma* must be a real, finite scalar greater than 1 for the following input modes: low speed temperature ratio, high speed temperature ratio, subsonic total temperature, supersonic total temperature, subsonic total pressure, and supersonic total pressure.

rayleigh_flow

Array of real numerical values for one Rayleigh line flow. This argument can be one of the following:

- Array of Mach numbers. This array must be a scalar or an array of *N* real numbers greater than or equal to 0. If *rayleigh_flow* and *gamma* are arrays, they must be the same size.

Use *rayleigh_flow* with *mtype* value 'mach'. Because 'mach' is the default of *mtype*, *mtype* is optional when this array is the input mode.

- Scalar value of temperature ratio. The temperature ratio is the local static temperature over the reference static temperature for sonic flow. *rayleigh_flow* must be a real scalar:

- Greater than or equal to 0 (at the Mach number equal 0 for low speeds or as Mach number approaches infinity for high speeds)
- Less than or equal to $1/4*(\gamma+1/\gamma)+1/2$ (at $mach = 1/\sqrt{\gamma}$)

Use *rayleigh_flow* with *mtype* values '*templo*' and '*temphi*'.

- Array of pressure ratios. The pressure ratio is the local static pressure over the reference static pressure for sonic flow. *rayleigh_flow* must be a scalar or array of real numbers less than or equal to $\gamma+1$ (at the Mach number equal 0). If *rayleigh_flow* and γ are arrays, they must be the same size.

Use *rayleigh_flow* with *mtype* value '*pres*'.

- Array of density ratios. The density ratio is the local density over the reference density for sonic flow. *rayleigh_flow* must be a scalar or array of real numbers. These numbers must be greater than or equal to:

$\gamma/(\gamma+1)$ (as Mach number approaches infinity)

If *rayleigh_flow* and γ are arrays, they must be the same size.

Use *rayleigh_flow* with *mtype* value '*dens*'.

- Array of velocity ratios. The velocity ratio is the local velocity over the reference velocity for sonic flow. *rayleigh_flow* must be a scalar or an array of N real numbers:

- Greater than or equal to 0
- Less than or equal to $(\gamma+1)/\gamma$ (as Mach number approaches infinity)

If *rayleigh_flow* and γ are both arrays, they must be the same size.

Use *rayleigh_flow* with *mtype* value '*velo*'.

- Scalar value of total temperature ratio. The total temperature ratio is the local stagnation temperature over the reference stagnation temperature for sonic flow. In subsonic mode, *rayleigh_flow* must be a real scalar:

- Greater than or equal to 0 (at the Mach number equal 0)
- Less than or equal to 1 (at the Mach number equal 1)

In supersonic mode, *rayleigh_flow* must be a real scalar:

- Greater than or equal to $(\gamma+1)^{2*(\gamma-1)/2}/(\gamma^{2*(1+(\gamma-1)/2)})$ (as Mach number approaches infinity)
- Less than or equal to 1 (at the Mach number equal 1)

Use *rayleigh_flow* with the *mtype* values '*totaltsub*' and '*totaltsup*'.

- Scalar value of total pressure ratio. The total pressure ratio is the local stagnation pressure over the reference stagnation pressure for sonic flow. In subsonic mode, *rayleigh_flow* must be a real scalar.

- Greater than or equal to 1 (at the Mach number equal 1)
- Less than or equal to $(1+\gamma)*(1+(\gamma-1)/2)^{-\gamma/(\gamma-1)}$ (at Mach number equal 0)

In supersonic mode, *rayleigh_flow* must be a real scalar greater than or equal to 1.

Use *rayleigh_flow* with *mtype* values 'totalpsub' and 'totalpsup'.

mtype

Input mode for the Rayleigh flow in *rayleigh_flow*.

Type	Description
'mach'	Default. Mach number.
'templo'	Low speed static temperature ratio. The low speed temperature ratio is the local static temperature over the reference sonic temperature. This ratio is for when the Mach number of the upstream flow is less than the critical Mach number of $1/\sqrt{\gamma}$.
'temphi'	High speed static temperature ratio. The high speed temperature ratio is the local static temperature over the reference sonic temperature. This ratio is for when the Mach number of the upstream flow is greater than the critical Mach number of $1/\sqrt{\gamma}$.
'pres'	Pressure ratio.
'dens'	Density ratio.
'velo'	Velocity ratio.
'totaltsub'	Subsonic total temperature ratio.
'totaltsup'	Supersonic total temperature ratio.
'totalpsub'	Subsonic total pressure ratio.
'totalpsup'	Supersonic total pressure ratio.

Output Arguments

All output ratios are static conditions over the sonic conditions. All outputs are the same size as the array inputs. If there are no array inputs, all outputs are scalars.

mach

Array of Mach numbers.

T

Array of temperature ratios. The temperature ratio is the local static temperature over the reference static temperature for sonic flow.

P

Array of pressure ratios. The pressure ratio is the local static pressure over the reference static pressure for sonic flow.

rho

Array of density ratio. The density ratio is the local density over the reference density for sonic flow.

velocity

Array of velocity ratios. The velocity ratio is the local velocity over the reference velocity for sonic flow.

T0

Array of total temperature ratios. The temperature ratio is the local stagnation temperature over the reference stagnation temperature for sonic flow.

P0

Array of total pressure ratios. The total pressure ratio is the local stagnation pressure over the reference stagnation pressure for sonic flow.

Examples**Calculate Rayleigh Line Flow Relations Given Air**

Calculate the Rayleigh line flow relations for air ($\gamma = 1.4$) for supersonic total pressure ratio 1.2.

```
[mach,T,P,rho,velocity,T0,P0] = flowrayleigh(1.4,1.2,'totalpsup')
```

```
mach =
```

```
    1.6397
```

```
T =
```

```
    0.6823
```

```
P =
```

```
    0.5038
```

```
rho =
```

```
    0.7383
```

```
velocity =
```

```
    1.3545
```

```
T0 =
```

```
    0.8744
```

```
P0 =
```

```
    1.2000
```

This example returns scalar values for $mach$, T , P , rho , $velocity$, $T0$, and $P0$.

Calculate Rayleigh Line Flow Relations for Specific Heat Ratios in Array

Calculate the Rayleigh line flow relations for gases with specific heat ratios given in the following 1 x 4 row array for the Mach number 0.5.

```
gamma = [1.3,1.33,1.4,1.67];
[mach,T,P,rho,velocity,T0,P0] = flowrayleigh(gamma,0.5)
```

```
mach =
    0.5000    0.5000    0.5000    0.5000
T =
    0.7533    0.7644    0.7901    0.8870
P =
    1.7358    1.7486    1.7778    1.8836
rho =
    2.3043    2.2876    2.2500    2.1236
velocity =
    0.4340    0.4371    0.4444    0.4709
T0 =
    0.6796    0.6832    0.6914    0.7201
P0 =
    1.1111    1.1121    1.1141    1.1202
```

This example returns a 1 x 4 row array for *mach*, *T*, *P*, *rho*, *velocity*, *T0*, and *P0*.

Calculate Rayleigh Line Flow Relations for Specific Heat Ratios and High Speed Temperature

Calculate the Rayleigh line flow relations for a specific heat ratio of 1.4 and high speed temperature ratio 0.70.

```
[mach,T,P,rho,velocity,T0,P0] = flowrayleigh(1.4,0.70,'temphi')
```

```
mach =
    1.6035
T =
    0.7000
P =
```



```

    0.5218
rho =
    0.7454
velocity =
    1.3416
T0 =
    0.8833
P0 =
    1.1777

```

This example returns scalar values for *mach*, *T*, *P*, *rho*, *velocity*, *T0*, and *P0*.

Calculate Rayleigh Line Flow Relations for Gases with Specific Heat Ratio and Static Pressure

Calculate the Rayleigh line flow relations for gases with specific heat ratio and static pressure ratio combinations as shown.

```

gamma = [1.3,1.4];
P = [0.13,1.7778];
[mach,T,P,rho,velocity,T0,P0] = flowrayleigh(gamma,P,'pres')

mach =
    3.5833    0.5000
T =
    0.2170    0.7901
P =
    0.1300    1.7778
rho =
    0.5991    2.2501
velocity =
    1.6692    0.4444
T0 =
    0.5521    0.6913
P0 =

```

7.4381 1.1141

This example returns a 1 x 2 array for *mach*, *T*, *P*, *rho*, *velocity*, *T θ* , and *P θ* each. The elements of each array correspond to the inputs element-wise.

References

1. James, J. E. A., *Gas Dynamics, Second Edition*, Allyn and Bacon, Inc, Boston, 1984.
2. *NACA Technical Report 1135*, 1953, National Advisory Committee on Aeronautics, Ames Research Staff, Moffett Field, Calif. Pages 667-671.

See Also

`flowfanno` | `flowisentropic` | `flownormalshock` | `flowprandtlmeyer`

Introduced in R2010a

forcesAndMoments

Class: Aero.FixedWing

Package: Aero

Calculate forces and moments of fixed-wing aircraft

Syntax

```
[F,M] = forcesAndMoments(aircraft,state)
```

Description

`[F,M] = forcesAndMoments(aircraft,state)` calculates the forces and moments of a fixed-wing aircraft, `aircraft`, based around a state `state`.

Input Arguments

aircraft — Aero.FixedWing object

scalar

Aero.FixedWing object, specified as a scalar.

state — Aero.FixedWing.State object

scalar

Aero.FixedWing.State object, specified as a scalar.

Output Arguments

F — Body forces

three-element vector

Body forces, returned as a three-element vector.

M — Body moments

three-element vector

Body moments, returned as a three-element vector.

Examples

Calculate Forces and Moments of a Cessna 182

Calculate the forces and moments of a Cessna 182.

```
[C182,CruiseState] = astC182();  
[F,M] = forcesAndMoments(C182, CruiseState)
```

```
F =  
-233.0908  
  0  
-0.3300  
  
M =  
1.0e+03 *  
  0  
  1.8739  
  0
```

See Also

`Aero.FixedWing` | `linearize` | `nonlinearDynamics`

Topics

“Determine Nonlinear Dynamics and Static Stability of Fixed-Wing Aircraft” on page 5-128

Introduced in R2021a

generatePatches (Aero.Body)

Generate patches for body with loaded face, vertex, and color data

Syntax

```
generatePatches(h, ax)  
h.generatePatches(ax)
```

Description

generatePatches(h, ax) and h.generatePatches(ax) generate patches for the animation body object h using the loaded face, vertex, and color data in ax.

Examples

Generate patches for b using the axes, ax.

```
b=Aero.Body;  
b.load('pa24-250_orange.ac', 'Ac3d');  
f = figure;  
ax = axes;  
b.generatePatches(ax);
```

See Also

load

Introduced in R2007a

GenerateRunScript (Aero.FlightGearAnimation)

Generate run script for FlightGear flight simulator

Syntax

```
GenerateRunScript(h)
h.GenerateRunScript
```

Description

GenerateRunScript(h) and h.GenerateRunScript generate a run script for FlightGear flight simulator using the following FlightGear animation object properties:

OutputFileName	Specify the name of the output file. The file name is the name of the command you will use to start FlightGear with these initial parameters. The default value is 'runfg.bat'.
FlightGearBaseDirectory	Specify the name of your FlightGear installation folder. The default value is 'C:\Applications\FlightGear'.
GeometryModelName	Specify the name of the folder containing the desired model geometry in the <i>FlightGear\data\Aircraft</i> folder. The default value is 'HL20'.
DestinationIpAddress	Specify your destination IP address. The default value is '127.0.0.1'.
DestinationPort	Specify your network flight dynamics model (fdm) port. This destination port should be an unused port that you can use when you launch FlightGear. The default value is '5502'.
AirportId	Specify the airport ID. The list of supported airports is available in the FlightGear interface, under Location . The default value is 'KSFO'.
RunwayId	Specify the runway ID. The default value is '10L'.
InitialAltitude	Specify the initial altitude of the aircraft, in feet. The default value is 7224 feet.
InitialHeading	Specify the initial heading of the aircraft, in degrees. The default value is 113 degrees.
OffsetDistance	Specify the offset distance of the aircraft from the airport, in miles. The default value is 4.72 miles.
OffsetAzimuth	Specify the offset azimuth of the aircraft, in degrees. The default value is 0 degrees.
InstallScenery	Direct FlightGear to automatically install required scenery while the simulator is running. This property requires a steady Internet connection. For Windows systems, you may encounter an error message while launching FlightGear with this option enabled. For more information, see "Installing Additional FlightGear Scenery" on page 2-42.

DisableShaders	Disable FlightGear shader options. Your computer built-in video card, such as NVIDIA cards, can conflict with FlightGear shaders. Consider using this property if you have this conflict.
Architecture	Specify the architecture on which the FlightGear software is running.

Examples

Create a run script, `runfg.bat`, to start FlightGear flight simulator using the default object settings:

```
h = fganimation
GenerateRunScript(h)
```

Create a run script, `myscript.bat`, to start FlightGear flight simulator using the default object settings:

```
h = fganimation
h.OutputFileName = 'myscript.bat'
GenerateRunScript(h)
```

See Also

[initialize](#) | [play](#) | [update](#)

Introduced in R2007a

geoc2geod

Convert geocentric latitude to geodetic latitude

Syntax

```
geodeticLatitude = geoc2geod(geocentricLatitude, radii)
[geodeticLatitude, height] = geoc2geod(geocentricLatitude, radii)
geodeticLatitude = geoc2geod(geocentricLatitude, radii, model)
[geodeticLatitude, height] = geoc2geod(geocentricLatitude, radii, model)
geodeticLatitude = geoc2geod(geocentricLatitude, radii, flattening,
equatorialRadius)
[geodeticLatitude, height] = geoc2geod(geocentricLatitude, radii, flattening,
equatorialRadius)
```

Description

`geodeticLatitude = geoc2geod(geocentricLatitude, radii)` and `[geodeticLatitude, height] = geoc2geod(geocentricLatitude, radii)` convert an array of geocentric latitudes and an array of radii from the center of the planet into an array of geodetic latitudes. The optional `height` returns the mean sea-level altitude (MSL).

`geodeticLatitude = geoc2geod(geocentricLatitude, radii, model)` and `[geodeticLatitude, height] = geoc2geod(geocentricLatitude, radii, model)` convert for a specific ellipsoid planet.

`geodeticLatitude = geoc2geod(geocentricLatitude, radii, flattening, equatorialRadius)` and `[geodeticLatitude, height] = geoc2geod(geocentricLatitude, radii, flattening, equatorialRadius)` convert for a custom ellipsoid planet defined by flattening and the equatorial radius.

This function has the limitation that this implementation generates a geodetic latitude that lies between ± 90 degrees.

Input Arguments

geocentricLatitude

Array of geocentric latitudes, in degrees. Latitude values can be any value. However, values of +90 and -90 may return unexpected values because of singularity at the poles.

radii

Array of radii from the center of the planet, in meters.

model

Specific ellipsoid planet. This function supports only 'WGS84'.

flattening

Custom ellipsoid planet defined by flattening.

equatorialRadius

Equatorial radius, in meters.

Output Arguments**geodeticLatitude**

Array of geodetic latitudes, in degrees.

height

Scalar of mean sea-level altitude (MSL), in meters.

Examples

Determine geodetic latitude given a geocentric latitude and radius:

```
[gd,h] = geoc2geod(45,6379136)
```

```
gd =
    45.1921
```

```
h =
    1.1718e+04
```

Determine geodetic latitude at multiple geocentric latitudes, given a radius, and specifying WGS84 ellipsoid model:

```
[gd,h] = geoc2geod([0 45 90],6379136,'WGS84')
```

```
gd =
     0    45.1921    90.0000
```

```
h =
    1.0e+04 *
    0.0999    1.1718    2.2384
```

Determine geodetic latitude at multiple geocentric latitudes, given a radius, and specifying custom ellipsoid model:

```
f = 1/196.877360;
Re = 3397000;
[gd,h] = geoc2geod([0 45 90],6379136,f,Re)
```

```
gd =
     0    45.1550    90.0000
```

```
h =
    1.0e+06 *
    2.9821    2.9908    2.9994
```

References

Jackson, E.B., *Manual for a Workstation-based Generic Flight Simulation Program (LaRCsim) Version 1.4*, NASA TM 110164, April 1995

Hedgley, D. R., Jr., *An Exact Transformation from Geocentric to Geodetic Coordinates for Nonzero Altitudes*, NASA TR R-458, March, 1976

Clynch, J. R.. "Radius of the Earth - Radii Used in Geodesy." Naval Postgraduate School, Monterey, California, 2002.

Stevens, B. L., and F. L. Lewis, *Aircraft Control and Simulation*, John Wiley & Sons, New York, NY, 1992

Edwards, C. H., and D. E. Penny, *Calculus and Analytical Geometry*, 2nd Edition, Prentice-Hall, Englewood Cliffs, NJ, 1986

See Also

ecef2lla | geod2geoc | lla2ecef

Introduced in R2006b

geocradius

Convert from geocentric latitude to radius of ellipsoid planet

Syntax

```
r = geocradius(lambda)
r = geocradius(lambda, model)
r = geocradius(lambda, f, Re)
```

Description

`r = geocradius(lambda)` estimates the radius, `r`, of an ellipsoid planet at a particular geocentric latitude, `lambda`. `lambda` is in degrees. `r` is in meters. The default ellipsoid planet is WGS84.

`r = geocradius(lambda, model)` is an alternate method for estimating the radius for a specific ellipsoid planet. Currently only 'WGS84' is supported for `model`.

`r = geocradius(lambda, f, Re)` is another alternate method for estimating the radius for a custom ellipsoid planet defined by flattening, `f`, and the equatorial radius, `Re`, in meters.

Examples

Determine radius at 45 degrees latitude:

```
r = geocradius(45)
```

```
r =
```

```
6.3674e+006
```

Determine radius at multiple latitudes:

```
r = geocradius([0 45 90])
```

```
r =
```

```
1.0e+006 *
```

```
6.3781    6.3674    6.3568
```

Determine radius at multiple latitudes, specifying WGS84 ellipsoid model:

```
r = geocradius([0 45 90], 'WGS84')
```

```
r =
```

```
1.0e+006 *
```

```
6.3781    6.3674    6.3568
```

Determine radius at multiple latitudes, specifying custom ellipsoid model:

```
f = 1/196.877360;  
Re = 3397000;  
r = geocradius([0 45 90], f, Re)
```

r =

```
1.0e+006 *  
3.3970    3.3883    3.3797
```

References

Stevens, B. L., and F. L. Lewis, *Aircraft Control and Simulation*, John Wiley & Sons, New York, NY, 1992

Zipfel, P. H., and D. E. Penny, *Modeling and Simulation of Aerospace Vehicle Dynamics*, AIAA Education Series, Reston, VA, 2000

See Also

geoc2geod | geod2geoc

Introduced in R2006b

geod2geoc

Convert geodetic latitude to geocentric latitude

Syntax

```
geocentricLatitude = geod2geoc(geodeticLatitude,height)
[geocentricLatitude,radii] = geod2geoc(geodeticLatitude,height)
geocentricLatitude = geod2geoc(geodeticLatitude,height,model)
[geocentricLatitude,radii] = geod2geoc(geodeticLatitude,height,model)
geocentricLatitude = geod2geoc(geodeticLatitude,height,flattening,
equatorialRadius)
[geocentricLatitude,radii] = geod2geoc(geodeticLatitude,height,flattening,
equatorialRadius)
```

Description

`geocentricLatitude = geod2geoc(geodeticLatitude,height)` and `[geocentricLatitude,radii] = geod2geoc(geodeticLatitude,height)` convert an array of geodetic latitudes, `geodeticLatitude`, and an array of mean sea level altitudes, `height`, into an array of geocentric latitudes, `geocentricLatitude`. The optional `radii` returns the radius from the center of the planet to the center of gravity.

`geocentricLatitude = geod2geoc(geodeticLatitude,height,model)` and `[geocentricLatitude,radii] = geod2geoc(geodeticLatitude,height,model)` convert from geodetic to geocentric latitude for a specific ellipsoid planet.

`geocentricLatitude = geod2geoc(geodeticLatitude,height,flattening, equatorialRadius)` and `[geocentricLatitude,radii] = geod2geoc(geodeticLatitude, height, flattening, equatorialRadius)` convert from geodetic to geocentric latitude for a custom ellipsoid planet defined by flattening, flattening, and the equatorial radius, `equatorialRadius`.

Input Arguments

geodeticLatitude

Array of geodetic latitudes, in degrees.

height

Scalar of mean sea-level altitude (MSL), in meters.

model

Specific ellipsoid planet. This function supports only 'WGS84'.

flattening

Custom ellipsoid planet defined by flattening.

equatorialRadius

Equatorial radius, in meters.

Output Arguments**geocentricLatitude**

Array of geocentric latitudes, in degrees. Latitude values can be any value. However, values of +90 and -90 may return unexpected values because of singularity at the poles.

radii

Array of radii from the center of the planet, in meters.

Examples

Determine geocentric latitude given a geodetic latitude and altitude:

```
[gc, r] = geod2geoc(45, 1000)
```

```
gc =  
    44.8076
```

```
r =  
    6.3685e+06
```

Determine geocentric latitude at multiple geodetic latitudes and altitudes, specifying WGS84 ellipsoid model:

```
[gc, r] = geod2geoc([0 45 90], [1000 0 2000], 'WGS84')
```

```
gc =  
     0    44.8076    90.0000
```

```
r =  
    1.0e+06 *  
    6.3791    6.3675    6.3588
```

Determine geocentric latitude at multiple geodetic latitudes, given an altitude and specifying custom ellipsoid model:

```
f = 1/196.877360;  
Re = 3397000;  
[gc, r] = geod2geoc([0 45 90], 2000, f, Re)
```

```
gc =  
     0    44.7084    90.0000
```

```
r =  
    1.0e+06 *  
    3.3990    3.3904    3.3817
```

Assumptions and Limitations

This implementation generates a geocentric latitude that lies between ± 90 degrees.

References

Stevens, B. L., and F. L. Lewis, *Aircraft Control and Simulation*, John Wiley & Sons, New York, NY, 1992

See Also

ecef2lla | geoc2geod | lla2ecef

Introduced in R2006b

geoidegm96

Calculate geoid height as determined from EGM96 Geopotential Model

Note `geoidegm96` will be removed in a future version. Use `geoidheight` instead.

Syntax

```
N = geoidegm96(lat, long)
N = geoidegm96(lat, long, action)
```

Description

`N = geoidegm96(lat, long)` calculates the geoid height as determined from the EGM96 Geopotential Model. It calculates geoid heights to 0.01 meters. This function interpolates geoid heights from a 15-minute grid of point values in the tide-free system, using the EGM96 Geopotential Model to the degree and order 360. The geoid undulations are relative to the WGS84 ellipsoid.

`N = geoidegm96(lat, long, action)` calculates the geoid height as determined from the EGM96 Geopotential Model. This function performs `action` if `latitude` or `longitude` are out of range.

Inputs required by `geoidegm96`:

<code>lat</code>	An array of <code>m</code> geocentric latitudes, in degrees, where north latitude is positive and south latitude is negative. <code>lat</code> must be of type single or double. If <code>lat</code> is not within the range -90 to 90, inclusive, this function wraps the value to be within the range.
<code>long</code>	An array of <code>m</code> geocentric longitudes, in degrees, where east longitude is positive and west longitude is negative. <code>long</code> must be of type single or double. If <code>long</code> is not within the range 0 to 360 inclusive, this function wraps the value to be within the range.
<code>action</code>	Action for out-of-range input. Specify if out-of-range input invokes a 'Warning', 'Error', or no action ('None'). The default is 'Warning'.

Examples

Calculate the geoid height at 42.4 degrees N latitude and 71.0 degrees E longitude.

```
N = geoidegm96( 42.4, 71.0)
```

Calculate the geoid height at two different locations, with out-of-range actions generating warnings.

```
N = geoidegm96( [39.3,33.4], [-77.2, 36.5])
```

Calculate the geoid height with latitude wrapping, with out-of-range actions displaying no warnings.


```
N = geoidegm96(100,150,'None')
```

Limitations

This function has the limitations of the 1996 Earth Geopotential Model. For more information, see <https://earth-info.nga.mil/GandG/wgs84/gravitymod/egm96/egm96.html>.

The WGS84 EGM96 geoid undulations have an error range of +/-0.5 to +/-1.0 meters worldwide.

References

NIMA TR8350.2: "Department of Defense World Geodetic System 1984, Its Definition and Relationship with Local Geodetic Systems."

NASA/TP-1998-206861: "The Development of the Joint NASA GSFC and NIMA Geopotential Model EGM96"

National Geospatial-Intelligence Agency Website: <https://earth-info.nga.mil/GandG/wgs84/gravitymod/egm96/egm96.html>

See Also

`gravitywgs84`

Introduced in R2007b

geoidheight

Calculate geoid height

Syntax

```
N = geoidheight(latitude,longitude)
N = geoidheight(latitude,longitude,modelname)
N = geoidheight(latitude,longitude,action)
N = geoidheight(latitude,longitude,modelname,action)
N = geoidheight(latitude,longitude,'custom',datafile)
N = geoidheight( ____,action)
```

Description

`N = geoidheight(latitude,longitude)` calculates the geoid height using the EGM96 Geopotential Model. For this geopotential model, the function calculates the geoid heights to an accuracy of 0.01 m and interpolates an array of m geoid heights at m geodetic latitudes, `latitude`, and m longitudes, `longitude`.

`N = geoidheight(latitude,longitude,modelname)` calculates the geoid height using the geopotential model, `modelname`.

`N = geoidheight(latitude,longitude,action)` calculates the geoid height and performs `action` if `latitude` or `longitude` are out of range.

`N = geoidheight(latitude,longitude,modelname,action)` calculates the geoid height using `modelname` and performs `action` if `latitude` or `longitude` are out of range.

`N = geoidheight(latitude,longitude,'custom',datafile)` calculates the geoid height using the custom model specified by `datafile`.

`N = geoidheight(____,action)` calculates the geoid height using the custom geopotential model and performs function performs `action` if `latitude` or `longitude` are out of range. Specify `action` as the last input argument preceded by any of the input argument combinations in the previous syntaxes.

Examples

Calculate EGM96 Geoid Height with Warning

Calculate the EGM96 geoid height at 42.4 degrees N latitude and 71.0 degrees W longitude. A warning, enabled by default, is returned for the out-of-range longitude value:

```
N = geoidheight(42.4,-71.0)
```

```
Warning: One or more longitude values exceed [0,360] range. Wrapping out of
range longitude values within 0 degrees and 360 degrees and continuing.
> In geoidheight>@()warning(message('aero:geoidheight:warnLongitudeWrap')) (line 324)
In geoidheight/checklongitude (line 328)
In geoidheight (line 166)
```

```
N =
    -28.3700
```

Calculate EGM2008 Geoid height at Two Locations with Error Action

Calculate the EGM2008 geoid height at two different locations. The function returns an error if the results are out of range:

```
N = geoidheight([39.3, 33.4],[77.2,36.5], 'egm2008', 'error')
```

```
N =
    -49.9440    23.6110
```

Calculate Custom Geoid Height at Two Locations

Calculate a custom geoid height at two different locations:

```
N = geoidheight([39.3,33.4],[-77.2,36.5], 'custom', ...
    'geoidegm96grid', 'none')
```

```
N =
    -33.0100    25.5500
```

Input Arguments

latitude — Geodetic latitudes

array

Geodetic latitudes, specified as an array of m geodetic latitudes, in degrees, where north latitude is positive and south latitude is negative.

If *latitude* is not within the range -90 to 90 , inclusive, this function wraps the value to be within the range when *action* is set to 'None' or 'Warning'. It does not wrap when *action* is set to 'Error'.

Data Types: double | single

longitude — Longitudes

array

Longitudes, specified as an array of m longitudes, in degrees, where east longitude is positive and west longitude is negative. If *longitude* is not within the range 0 to 360 inclusive, this function wraps the value to be within the range.

If *longitude* is not within the range -90 to 90 , inclusive, this function wraps the value to be within the range when *action* is set to 'None' or 'Warning'. It does not wrap when *action* is set to 'Error'.

Data Types: double | single

modelName — Geopotential model

'EGM96' (default) | 'EGM2008' | 'custom'

Geopotential model, specified as:

Geopotential Model	Description
'EGM96'	EGM96 Geopotential Model to degree and order 360. This model uses a 15-minute grid of point values in the tide-free system. This function calculates geoid heights to an accuracy of 0.01 m for this model.
'EGM2008'	EGM2008 Geopotential Model to degree and order 2159. This model uses a 2.5-minute grid of point values in the tide-free system. This function calculates geoid heights to an accuracy of 0.001 m for this model. Note This function requires that you download EGM2008 Geopotential Model data with the Add-On Explorer. For more information, see <code>aeroDataPackage</code> .

Data Types: char | string

datafile — Custom geopotential model definitions

scalar

Custom geopotential model definitions, specified as a scalar file of definitions for a custom geopotential model.

This file must contain these variables:

Variable	Description
'latbp'	Array of geodetic latitude breakpoints.
'lonbp'	Array of longitude breakpoints.
'grid'	Table of geoid height values.
'windowSize'	Even integer scalar greater than 2 for the number of interpolation points.

Data Types: char | string

action — Action

'Warning' (default) | 'Error' | 'None'

Action for out-of-range input, specified as:

- 'Error' — Displays warning and indicates that the input is out of range
- 'Warning' — Displays error and indicates that the input is out of range
- 'None' — Does not display warning or error

Data Types: char | string

Output Arguments**N — Geoid heights**

array | same data type as latitude argument

Geoid heights, returned as an array of M geoid heights, in meters.

Tips

- This function interpolates geoid heights from a grid of point values in the tide-free system.
- When using the EGM96 Model, this function has the limitations of the 1996 Earth Geopotential Model.
- When using the EGM2008 Model, this function has the limitations of the 2008 Earth Geopotential Model.
- The interpolation scheme wraps over the poles to allow for geoid height calculations at and near pole locations.
- The geoid undulations for the EGM96 and EGM2008 models are relative to the WGS84 ellipsoid.
- The WGS84 EGM96 geoid undulations have an error range of +/- 0.5 to +/- 1.0 m worldwide.

References

- [1] Vallado, D. A. "Fundamentals of Astrodynamics and Applications." McGraw-Hill, New York, 1997.
- [2] NIMA TR8350.2: "Department of Defense World Geodetic System 1984, Its Definition and Relationship with Local Geodetic Systems."

See Also

`gravitiesphericalharmonic` | `gravitywgs84`

External Websites

National Geospatial-Intelligence Agency Web site: <http://earth-info.nga.mil/GandG/publications/vertdatum.html>

Introduced in R2010b

Geometry (Aero.Geometry)

Construct 3-D geometry for use with animation object

Syntax

```
h = Aero.Geometry
```

Description

`h = Aero.Geometry` defines a 3-D geometry for use with an animation object.

See `Aero.Geometry` for further details.

See Also

`Aero.Geometry`

Introduced in R2007a

getCoefficient

Class: Aero.FixedWing

Package: Aero

Get coefficient value for Aero.FixedWing object

Syntax

```
value = getCoefficient(aircraft, stateOutput, stateVariable)
```

```
value = getCoefficient( ____, Name, Value)
```

Description

`value = getCoefficient(aircraft, stateOutput, stateVariable)` gets the coefficient value value from the coefficient specified by `stateOutput` and `stateVariable`.

`value = getCoefficient(____, Name, Value)` gets the coefficient value using one or more `Name, Value` pairs.

Input Arguments

aircraft — Aero.FixedWing object

scalar

Aero.FixedWing object, specified as a scalar.

stateOutput — Valid state output

vector of strings | character array

Valid state output, specified in a vector of strings or character array. For more information, see `Aero.FixedWing.Coefficient`.

Data Types: `string` | `char`

stateVariable — Valid state variable

vector

Valid state variable, specified in a vector of strings or character array. Valid state variables depend on the coefficients defined on the object. For more information, see `Aero.FixedWing.Coefficient`.

Data Types: `string` | `char`

Name-Value Pair Arguments

Specify optional comma-separated pairs of `Name, Value` arguments. `Name` is the argument name and `Value` is the corresponding value. `Name` must appear inside quotes. You can specify several name and value pair arguments in any order as `Name1, Value1, ..., NameN, ValueN`.

Example: `'Component', 'Hello'`

State — Aero.FixedWing.State object to calculate numeric values of Simulink.LookupTable objects

scalar

Aero.FixedWing.State object to calculate numeric values of Simulink.LookupTable objects, specified as a scalar.

Data Types: double

Component — Valid component name

scalar string

Valid component name, specified as a scalar string. Valid component names depend on the 'Name' property of an object and all its subcomponents. The default component is the current object.

Data Types: char | string

Output Arguments**value — Coefficient values**

vector

Coefficient values, returned as a value of the same size as stateOutput and stateVariable. Vector contents depend on the type of coefficients in the vector.

Type of Coefficients in Vector	Vector
All numeric constants	Numeric vector
Simulink.LookupTable objects	Vector of Simulink.LookupTable objects
Mix of numeric constants and Simulink.LookupTable objects	Vector of cells
Simulink.LookupTable objects with state included	Numeric vector

Examples**Get Coefficient for Angle of Attack**

Get a CD_alpha on an Aero.FixedWing object.

```
C182 = astC182();
CD_alpha = getCoefficient(C182, "CD", "Alpha")
```

```
CD_alpha =
    0.1210
```

Get Vector of Coefficient Values

Get a vector of coefficient values on a component within an Aero.FixedWing object.


```
C182 = astC182();
coeffs = getCoefficient(C182,{'CY'; 'Cm'},{'Aileron';'Aileron'},'Component','Aileron')
```

Get Simulink.LookupTable Coefficient

Get a `Simulink.LookupTable` coefficient from an `Aero.FixedWing` object.

```
SkyHogg = astSkyHogg();
Cl_zero = getCoefficient(SkyHogg, "Cl", "Zero")
```

```
Cl_zero =
    0
```

Get Simulink.LookupTable Coefficient with State

Get a `Simulink.LookupTable` coefficient from an `Aero.FixedWing` object and include a state.

```
[SkyHogg, CruiseState] = astSkyHogg();
Cl_zero = getCoefficient(SkyHogg, "Cl", "Zero", "State", CruiseState)
```

```
Cl_zero =
    0
```

Limitations

- Each vector of inputs `stateOutput` and `stateVariable` must be the same length.
- When used with `Simulink.LookupTable` objects, this method requires a Simulink license.

See Also

`Aero.FixedWing` | `Simulink.LookupTable` | `setCoefficient`

Introduced in R2021a

getCoefficient

Class: Aero.FixedWing.Coefficient

Package: Aero

Get coefficient values from fixed-wing coefficient object

Syntax

```
value = getCoefficient(fixedWingCoefficient, stateOutput, stateVariable)
value = getCoefficient( ____, Name, Value)
```

Description

`value = getCoefficient(fixedWingCoefficient, stateOutput, stateVariable)` gets the coefficient value `value` from the coefficient specified by `stateOutput` and `stateVariable`.

`value = getCoefficient(____, Name, Value)` gets the coefficient value using one or more `Name, Value` pairs.

Input Arguments

fixedWingCoefficient — Aero.FixedWing.Coefficient object for which to get coefficient
scalar

Aero.FixedWing.Coefficient object for which to get coefficient, specified as a scalar.

stateOutput — State output
6-by-1 vector

State output, specified as a 6-by-1 vector where each entry is a valid state output. For more information on state outputs, see Aero.FixedWing.Coefficient.

Data Types: char | string

stateVariable — State variable
vector

State variable, specified as a vector where each entry is a valid state variable. Valid state variables depend on the coefficients defined on the object. For more information on fixed-wing states, see Aero.FixedWing.State.

Data Types: char | string

Name-Value Pair Arguments

Specify optional comma-separated pairs of `Name, Value` arguments. `Name` is the argument name and `Value` is the corresponding value. `Name` must appear inside quotes. You can specify several name and value pair arguments in any order as `Name1, Value1, ..., NameN, ValueN`.

Example: 'State', 'on'

State — Aero.FixedWing.State object

scalar | Aero.FixedWing.State object

Aero.FixedWing.State object, specified as a scalar, that calculates the numeric values of any Simulink.LookupTable objects. Including an Aero.FixedWing.State guarantees value is a numeric vector.

Data Types: char | string

Component — Component name

string

Component name, specified as a string. Valid component names depend on the object properties and all subcomponents on the object. The default component name is the current object.

Data Types: char | string

Output Arguments**value — Coefficient values**

vector

Coefficient values, returned as a vector of the same size as stateOutput and stateVariable. Vector contents depend on the type of coefficients in the vector.

Type of Coefficients in Vector	Vector
All numeric constants	Numeric vector
Simulink.LookupTable objects	Vector of Simulink.LookupTable objects
Mix of numeric constants and Simulink.LookupTable objects	Vector of cells
Simulink.LookupTable objects with state included	Numeric vector

Examples**Get CD_alpha on Fixed-Wing Coefficient Object**

Get a CD_alpha on a fixed-wing coefficient object.

```
C182 = astC182();
CD_alpha = getCoefficient(C182, "CD", "Alpha")
```

```
CD_alpha =
    0.1210
```

Get Vector of Coefficient Values

Get a vector of coefficient values on a component within a fixed-wing coefficient object.

```
C182 = astC182();
coeffs = getCoefficient(C182, ["CY"; "Cm"], ["Aileron"; "Aileron"], "Component", "Aileron")

coeffs =

     0     0
```

Get Simulink.LookupTable Coefficient

Get a `Simulink.LookupTable` coefficient from a fixed-wing coefficient object.

```
SkyHogg = astSkyHogg();
Cl_zero = getCoefficient(SkyHogg, "Cl", "Zero")

Cl_zero =

     0
```

Get Simulink.LookupTable Coefficient and Include State

Get a `Simulink.LookupTable` coefficient from a fixed-wing coefficient object and include a state.

```
[SkyHogg, CruiseState] = astSkyHogg();
Cl_zero = getCoefficient(SkyHogg, "Cl", "Zero", "State", CruiseState)

Cl_zero =

     0
```

Limitations

- The vectors for the `stateOutput`, `stateVariable`, and `value` arguments must be the same length.
- When used with `Simulink.LookupTable` objects, this method requires a Simulink license.

See Also

[Aero.FixedWing](#) | [getCoefficient](#) | [setCoefficient](#)

Introduced in R2021a

getCoefficient

Class: Aero.FixedWing.Surface

Package: Aero

Get coefficient for fixed-wing surface object

Syntax

```
value = getCoefficient(fixedWingSurface, stateOutput, stateVariable)
value = getCoefficient( ____, Name, Value)
```

Description

`value = getCoefficient(fixedWingSurface, stateOutput, stateVariable)` gets the coefficient value `value` from the coefficient specified by `stateOutput` and `stateVariable`.

`value = getCoefficient(____, Name, Value)` gets the coefficient value using one or more `Name, Value` pairs.

Input Arguments

fixedWingSurface — Aero.FixedWing.Surface object for which to get coefficient

scalar

Aero.FixedWing.Surface object for which to get coefficient, specified as a scalar.

stateOutput — State output

6-by-1 vector

State output, specified as a 6-by-1 vector where each entry is a valid state output. For more information on state outputs, see Aero.FixedWing.Coefficient.

Data Types: char | string

stateVariable — State variable

vector

State variable, specified as a vector where each entry is a valid state variable. Valid state variables depend on the coefficients defined on the object. For more information on fixed-wing states, see Aero.FixedWing.State.

Data Types: char | string

Name-Value Pair Arguments

Specify optional comma-separated pairs of `Name, Value` arguments. `Name` is the argument name and `Value` is the corresponding value. `Name` must appear inside quotes. You can specify several name and value pair arguments in any order as `Name1, Value1, ..., NameN, ValueN`.

Example: 'Component', 'Hello'

State — Aero.FixedWing.State object to calculate numeric values of Simulink.LookupTable objects

scalar

Aero.FixedWing.State object to calculate numeric values of Simulink.LookupTable objects, specified as a scalar.

Data Types: double

Component — Valid component Name

scalar

Valid component name, specified as a scalar string. Valid component names depend on the 'Name' property of an object and all its subcomponents. The default component is the current object.

Data Types: char | string

Output Arguments**value — Coefficient values**

vector

Coefficient values, returned as a vector of the same size as stateOutput and stateVariable. Vector contents depend on the type of coefficients in the vector.

Type of Coefficients in Vector	Vector
All numeric constants	Numeric vector
Simulink.LookupTable objects	Vector of Simulink.LookupTable objects
Mix of numeric constants and Simulink.LookupTable objects	Vector of cells
Simulink.LookupTable objects with state included	Numeric vector

See Also

Aero.FixedWing | Aero.FixedWing.Coefficient | Aero.FixedWing.Surface | Aero.FixedWing.Thrust | setCoefficient

Introduced in R2021a

getCoefficient

Class: Aero.FixedWing.Thrust

Package: Aero

Get coefficient for fixed-wing thrust object

Syntax

```
value = getCoefficient(fixedWingThrust, stateOutput, stateVariable)
value = getCoefficient( ____, Name, Value)
```

Description

`value = getCoefficient(fixedWingThrust, stateOutput, stateVariable)` gets the coefficient value `value` from the coefficient specified by `stateOutput` and `stateVariable`.

`value = getCoefficient(____, Name, Value)` gets the coefficient value using one or more `Name, Value` pairs.

Input Arguments

fixedWingThrust — Aero.FixedWing.Thrust object for which to get coefficient

scalar

Aero.FixedWing.Thrust object for which to get coefficient, specified as a scalar.

stateOutput — State output

6-by-1 vector

State output, specified as a 6-by-1 vector where each entry is a valid state output. For more information on state outputs, see Aero.FixedWing.Coefficient.

Data Types: char | string

stateVariable — State variable

vector

State variable, specified as a vector where each entry is a valid state variable. Valid state variables depend on the coefficients defined on the object. For more information on fixed-wing states, see Aero.FixedWing.State.

Data Types: char | string

Name-Value Pair Arguments

Specify optional comma-separated pairs of `Name, Value` arguments. `Name` is the argument name and `Value` is the corresponding value. `Name` must appear inside quotes. You can specify several name and value pair arguments in any order as `Name1, Value1, ..., NameN, ValueN`.

Example: 'Component', 'Hello'

State — Aero.FixedWing.State object to calculate numeric values of Simulink.LookupTable objects

scalar

Aero.FixedWing.State object to calculate numeric values of Simulink.LookupTable objects, specified as a scalar.

Data Types: double

Component — Valid component name

scalar

Valid component name, specified as a scalar string. Valid component names depend on the 'Name' property of an object and all its subcomponents. The default component is the current object.

Data Types: char | string

Output Arguments**value — Coefficient values**

vector

Coefficient values, specified as a vector of the same size as stateOutput and stateVariable. Vector contents depend on the type of coefficients in the vector.

Type of Coefficients in Vector	Vector Type
All numeric constants	Numeric vector
Simulink.LookupTable objects	Vector of Simulink.LookupTable objects
Mix of numeric constants and Simulink.LookupTable objects	Vector of cells
Simulink.LookupTable objects with state included	Numeric vector

See Also**Topics**

Aero.FixedWing
Aero.FixedWing.Thrust
setCoefficient
Simulink.LookupTable

Introduced in R2021a

getControlStates

Class: Aero.FixedWing

Package: Aero

Get control states for Aero.FixedWing object

Syntax

```
control_states = getControlStates(aircraft)
```

Description

control_states = getControlStates(aircraft) gets Aero.Aircraft.ControlState control states for the Aero.FixedWing object aircraft.

Input Arguments

aircraft — Aero.FixedWing coefficient object

scalar | Aero.FixedWing | Aero.FixedWing.Surface | Aero.FixedWing.Control | Aero.FixedWing.Thrust

Aero.FixedWing coefficient object, specified as a scalar of type Aero.FixedWing, Aero.FixedWing.Surface, Aero.FixedWing.Control, or Aero.FixedWing.Thrust.

Output Arguments

control_states — Aero.Aircraft.ControlState objects

vector

Aero.Aircraft.ControlState objects, returned as a vector.

Examples

Get Aero.Aircraft.ControlState Control States

Get the control states for an Aero.FixedWing object.

```
C182 = astC182();
ctrlStates = getControlStates(C182)

ctrlStates =
    1×4 ControlState array with properties:

    Position
    MaximumValue
    MinimumValue
    DependsOn
    Settable
```

DeflectionAngle
Properties

See Also

`Aero.Aircraft.ControlState` | `Aero.FixedWing` | `Aero.FixedWing.State`

Introduced in R2021a

getControlStates

Class: Aero.FixedWing.Surface

Package: Aero

Get control states for Aero.FixedWing.Surface object

Syntax

```
control_states = getControlStates(surface)
```

Description

`control_states = getControlStates(surface)` gets control states, `control_states`, for the Aero.FixedWing.Surface object, `surface`.

Input Arguments

surface — Aero.FixedWing.Surface object

scalar

Aero.FixedWing.Surface object, specified as a scalar.

Output Arguments

control_states — Aero.Aircraft.ControlState objects

vector

Aero.Aircraft.ControlState objects, returned as a vector.

See Also

Aero.Aircraft.ControlState | Aero.FixedWing | Aero.FixedWing.State | getControlStates

Introduced in R2021a

getControlStates

Class: Aero.FixedWing.Thrust

Package: Aero

Get control states for Aero.FixedWing.Thrust object

Syntax

```
control_states = getControlStates(thrust)
```

Description

`control_states = getControlStates(thrust)` gets control states, `control_states`, for the Aero.FixedWing.Thrust object, `thrust`.

Input Arguments

thrust — Aero.FixedWing.Thrust object

scalar

Aero.FixedWing.Thrust object, specified as a scalar.

Output Arguments

control_states — Aero.Aircraft.ControlState objects

vector

Aero.Aircraft.ControlState objects, returned as a vector.

See Also

Aero.Aircraft.ControlState | Aero.FixedWing | Aero.FixedWing.State |
getControlStates

Introduced in R2021a

getState

Class: Aero.FixedWing.State

Package: Aero

Get state value

Syntax

```
value = getState(state, statename)
```

Description

`value = getState(state, statename)` gets the state value from the state name `statename`.

Input Arguments

state — Aero.FixedWing.State object

scalar

Aero.FixedWing.State object, specified as a scalar.

statename — State name

vector

State names, specified as a vector. For more information on state names, see the Aero.FixedWing.State “Properties” on page 4-59.

Data Types: char | string

Output Arguments

value — State values

vector

State values, returned as a vector.

- If the states are all scalar constants, `value` is a numeric vector.
- If one of more states are not scalar constants, `value` is a cell vector.

Examples

Get Angle of Attack from Cruise State

Get the angle of attack from a cruise state.

```
[C182, CruiseState] = astC182();  
alpha = getState(CruiseState, 'Alpha')
```

```
alpha =  
    0
```

Get U, V, and W Velocity Components

Get the U , V , and W velocity components from a cruise state.

```
[C182, CruiseState] = astC182();  
uvw = getState(CruiseState, {'U', 'V', 'W'})
```

```
uvw =  
    220.1000         0         0
```

See Also

[Aero.FixedWing.State](#) | [setState](#) | [setupControlStates](#)

Introduced in R2021a

gimbal

Add gimbal to satellite or ground station

Syntax

```
gimbal(parent)
gimbal(parent,Name,Value)
gimbal( ___ )
```

Description

`gimbal(parent)` adds a default Gimbal object to `parent`, which can be a satellite, ground station, or gimbal. A gimbal can dynamically change orientation independent of the parent. Transmitters, receivers, and conical sensors can be mounted on the gimbals.

`gimbal(parent,Name,Value)` specifies options using one or more name-value arguments.

`gim = gimbal(___)` returns a handle to the added gimbal. Specify any input argument combination from previous syntaxes.

Input Arguments

parent — Element of scenario to which gimbal is added

Satellite object | GroundStation object | Gimbal object

Element of scenario to which the gimbal is added, specified as a `Satellite`, `GroundStation`, or `Gimbal` object.

Name-Value Pair Arguments

Specify optional comma-separated pairs of `Name`, `Value` arguments. `Name` is the argument name and `Value` is the corresponding value. `Name` must appear inside quotes. You can specify several name and value pair arguments in any order as `Name1,Value1,...,NameN,ValueN`.

Example: `'MountingAngle',[20; 35; 10]` sets the yaw, pitch, and roll angles of gimbal to 20, 35, and 10 degrees, respectively.

Name — gimbal name

"gimbal_idx" (default) | string scalar | string vector | character vector | cell array of character vectors

You can set this property only when calling `gimbal`. After you call `gimbal`, this property is read-only.

`gimbal name`, specified as a comma-separated pair consisting of `'Name'` and a string scalar, string vector, character vector or a cell array of character vectors.

- If only one gimbal is added, specify `Name` as a string scalar or a character vector.
- If multiple gimbals are added, specify `Name` as a string vector or a cell array of character vectors. The number of elements in the string vector or cell array must be equal to the number of satellites being added.

In the default value, *idx* is the count of the gimbal added by the `gimbal` object function. If another gimbal of the same name exists, a suffix *_idx₂* is added, where *idx₂* is an integer that is incremented by 1 starting from 1 until the name duplication is resolved.

Data Types: `char` | `string`

MountingLocation – Mounting location with respect to parent

`[0; 0; 0]` (default) | three-element row vector of positive numbers

Mounting location with respect to the parent object, specified as a three-element row vector of positive numbers in meters. The position vector is specified in the body frame of the input parent.

MountingAngles – Mounting orientation with respect to parent object

`[0; 0; 0]` (default) | three-element row vector of positive numbers

Mounting orientation with respect to parent object, specified as a three-element row vector of positive numbers in degrees. The elements of the vector correspond to yaw, pitch, and roll in that order. Yaw, pitch, and roll are positive rotations about the parent's *z* - axis, intermediate *y* - axis and intermediate *x* - axis of the parent.

Example: `[0; 30; 60]`

Output Arguments**gim – Gimbal**

Gimbal object

Gimbal attached to parent, returned as a `Gimbal` object.

See Also**Objects**

`satelliteScenario` | `satelliteScenarioViewer`

Functions

`access` | `conicalSensor` | `groundStation` | `hide` | `play` | `satellite` | `show`

Topics

“Satellite Scenario Key Concepts” on page 2-61

Introduced in R2021a

Gimbal

Gimbal object belonging to satellite scenario

Description

The `Gimbal` defines a gimbal object belonging to a satellite scenario.

Creation

You can create a `Gimbal` object using the `gimbal` object function of the `Satellite` or `GroundStation`.

Properties

Name — Gimbal name

"Gimbal *idx*" (default) | string scalar | string vector | character vector | cell array of character vectors

You can set this property only when calling `Gimbal`. After you call `Gimbal`, this property is read-only.

Gimbal name, specified as a comma-separated pair consisting of 'Name' and a string scalar, string vector, character vector or a cell array of character vectors.

- If only one Gimbal is added, specify Name as a string scalar or a character vector.
- If multiple Gimbals are added, specify Name as a string vector or a cell array of character vectors. The number of elements in the string vector or cell array must be equal to the number of satellites being added.

In the default value, *idx* is the count of the Gimbal added by the `Gimbal` object function. If another Gimbal of the same name exists, a suffix *_idx₂* is added, where *idx₂* is an integer that is incremented by 1 starting from 1 until the name duplication is resolved.

Data Types: char | string

ID — Gimbal ID assigned by simulator

real positive scalar

This property is set internally by the simulator and is read-only.

Gimbal ID assigned by the simulator, specified as a positive scalar.

MountingLocation — Mounting location with respect to parent

[0; 0; 0] (default) | three-element row vector of positive numbers

Mounting location with respect to the parent object, specified as a three-element row vector of positive numbers in meters. The position vector is specified in the body frame of the input parent.

MountingAngles — Mounting orientation with respect to parent object

[0; 0; 0] (default) | three-element row vector of positive numbers

Mounting orientation with respect to parent object, specified as a three-element row vector of positive numbers in degrees. The elements of the vector correspond to yaw, pitch, and roll in that order. Yaw, pitch, and roll are positive rotations about the parent's z - axis, intermediate y - axis and intermediate x - axis of the parent.

Example: [0; 30; 60]

ConicalSensors – Conical sensors

row vector of conical sensors

You can set this property only when calling `conicalSensor`. After you call `conicalSensor`, this property is read-only.

Conical sensors attached to the Gimbal, specified as a row vector of conical sensors.

Object Functions

<code>conicalSensor</code>	Add conical sensor to satellite scenario
<code>pointAt</code>	Target at which entity must be pointed
<code>gimbalAngles</code>	Steering angles of gimbal

See Also**Objects**

`satelliteScenario` | `satelliteScenarioViewer`

Functions

`access` | `conicalSensor` | `groundStation` | `hide` | `play` | `satellite` | `show`

Topics

“Satellite Scenario Key Concepts” on page 2-61

Introduced in R2021a

gimbalAngles

Steering angles of gimbal

Syntax

```
az = gimbalAngles(gim)
[az,el] = gimbalAngles(gim)
[az,el,timeOut] = gimbalAngles(gim)
[ ___ ] = gimbalAngles(gim,timeIn)
```

Description

`az = gimbalAngles(gim)` returns the steering azimuth of the specified gimbal., in degrees. The gimbal is steered to the desired pointing direction by first rotating it about its body *z* - axis (steering azimuth) and secondly rotating it about its body *y* - axis (steering elevation).

`[az,el] = gimbalAngles(gim)` returns the steering azimuth and steering elevation of the specified gimbal.

`[az,el,timeOut] = gimbalAngles(gim)` returns the steering azimuth and steering elevation of the gimbal and the corresponding time in UTC.

`[___] = gimbalAngles(gim,timeIn)` returns the steering azimuth and steering elevation (depending on the specified output arguments) of the gimbal at the specified time. If you do not specify a time zone, the time zone is assumed to be Universal Time Coordinated (UTC).

Input Arguments

gim – Gimbal

Gimbal object

Gimbal whose steering angle is being calculated, specified as a `Gimbal` object.

Output Arguments

az – Azimuth angles

scalar | vector

Azimuth angles of target in the local azimuth, elevation and range (AER) system, returned as a scalar or vector. Azimuths are measured clockwise from North. Values are specified in degrees in the interval $[0, 360)$. The vector elements correspond to the time samples from the satellite scenario `StartTime` to `StopTime` properties, as specified by the `SampleTime` property. The azimuth angle is defined in the North-East-Down (NED) frame of (and centered at) `objIn` such that 0 degrees is North, 90 degrees is East, 180 degrees is South, and 270 degrees is West.

el – Elevation angles

scalar | vector

Elevation angles of target in the local AER system, returned as a scalar or vector. Elevations are measured with respect to a plane that is perpendicular to the normal of the surface of the earth. If `objIn` is on the surface of the Earth, then the plane is tangent to the Earth.

Values are specified in degrees in the closed interval [0 180]. The vector elements correspond to the time samples from the satellite scenario `StartTime` to `StopTime` properties, as specified by the `SampleTime` property. The elevation angle is defined in the NED frame of (and centered at) `objIn` such that 0 deg implies target is on the North East (NE) plane, 90 degrees implies target is directly above `objIn`, and -90 degrees implies target is directly below `objIn`.

timeOut — Time samples between start and stop time of scenario

scalar | vector | matrix | *N*-D array

Time samples between start and stop time of the scenario, returned as a scalar, vector, matrix, or *N*-D array. If `az` and `el` histories are returned

See Also

Objects

`satelliteScenario` | `satelliteScenarioViewer`

Functions

`conicalSensor` | `groundStation` | `hide` | `play` | `show`

Topics

“Satellite Scenario Key Concepts” on page 2-61

Introduced in R2021a

gravitycentrifugal

Implement centrifugal effect of planetary gravity

Syntax

```
[gx gy gz] = gravitycentrifugal(planet_coordinates)
[gx gy gz] = gravitycentrifugal(planet_coordinates, model )
[gx gy gz] = gravitycentrifugal(planet_coordinates, 'Custom',
rotational_rate)
```

Description

`[gx gy gz] = gravitycentrifugal(planet_coordinates)` implements the mathematical representation of centrifugal effect for planetary gravity based on planetary rotation rate. This function calculates arrays of N gravity values in the x -axis, y -axis, and z -axis of the Planet-Centered Planet-Fixed coordinates for the planet. It performs these calculations using *planet_coordinates*, an M -by-3 array of Planet-Centered Planet-Fixed coordinates. You use centrifugal force in rotating or noninertial coordinate systems. Gravity centrifugal effect values are greatest at the equator of a planet.

`[gx gy gz] = gravitycentrifugal(planet_coordinates, model)` implements the mathematical representation of centrifugal effect based on planetary gravitational potential for the planetary model, *model*.

`[gx gy gz] = gravitycentrifugal(planet_coordinates, 'Custom', rotational_rate)` implements the mathematical representation of centrifugal effect based on planetary gravitational potential using the custom rotational rate, *rotational_rate*.

Input Arguments

planet_coordinates

M -by-3 array of Planet-Centered Planet-Fixed coordinates in meters. The z -axis is positive toward the North Pole. If *model* is 'Earth', the planet coordinates are ECEF coordinates.

model

Planetary model. Default is 'Earth'. Specify one:

- 'Mercury'
- 'Venus'
- 'Earth'
- 'Moon'
- 'Mars'
- 'Jupiter'
- 'Saturn'
- 'Uranus'

- 'Neptune'
- 'Custom'

'Custom' requires that you specify your own planetary model using the *rotational_rate* parameter.

rotational_rate

Scalar value that specifies the planetary rotational rate in radians per second. Specify this parameter only if *model* has the value 'Custom'.

Output Arguments

gx

Array of *M* gravity values in the x-axis of the Planet-Centered Planet-Fixed coordinates in meters per second squared (m/s²).

gy

Array of *M* gravity values in the y-axis of the Planet-Centered Planet-Fixed coordinates in meters per second squared (m/s²).

gz

Array of *M* gravity values in the z-axis of the Planet-Centered Planet-Fixed coordinates in meters per second squared (m/s²).

Examples

Calculate the centrifugal effect of Earth gravity in the x-axis at the equator on the surface of Earth:

```
gx = gravitycentrifugal( [-6378.1363e3 0 0] )
```

Calculate the centrifugal effect of Mars gravity at 15000 m over the equator and 11000 m over the North Pole:

```
p = [2412.648e3 -2412.648e3 0; 0 0 3376.2e3]
[ gx, gy, gz ] = gravitycentrifugal( p, 'Mars' )
```

Calculate the precessing centrifugal effect of gravity for Earth at 15000 m over the equator and 11000 m over the North Pole. This example uses a custom planetary model at Julian date 2451545:

```
p          = [2412.648e3 -2412.648e3 0; 0 0 3376e3]
% Set julian date to January 1, 2000 at noon GMT
JD         = 2451545
% Calculate precession rate in right ascension in meters
pres_RA   = 7.086e-12 + 4.3e-15*(JD - 2451545)/36525
% Calculate the rotational rate in a precessing reference
% frame
Omega     = 7.2921151467e-5 + pres_RA
[ gx, gy, gz ] = gravitycentrifugal( p, 'custom', Omega )
```

See Also

gravitysphericalharmonic | gravitywgs84 | gravityzonal

Introduced in R2010a

gravitysphericalharmonic

Implement spherical harmonic representation of planetary gravity

Syntax

```
[gx gy gz] = gravitysphericalharmonic(planet_coordinates)
[gx gy gz] = gravitysphericalharmonic(planet_coordinates, model)
[gx gy gz] = gravitysphericalharmonic(planet_coordinates, degree)
[gx gy gz] = gravitysphericalharmonic(planet_coordinates, model, degree)
[gx gy gz] = gravitysphericalharmonic(planet_coordinates, model, degree,
action)
[gx gy gz] = gravitysphericalharmonic(planet_coordinates, 'Custom', degree,
{datafile dfreader}, action)
```

Description

`[gx gy gz] = gravitysphericalharmonic(planet_coordinates)` implements the mathematical representation of spherical harmonic planetary gravity based on planetary gravitational potential. This function calculates arrays of N gravity values in the x-axis, y-axis, and z-axis of the Planet-Centered Planet-Fixed coordinates for the planet. It performs these calculations using `planet_coordinates`, an M -by-3 array of Planet-Centered Planet-Fixed coordinates. By default, this function assumes 120th degree and order spherical coefficients for the 'EGM2008' (Earth) planetary model.

`[gx gy gz] = gravitysphericalharmonic(planet_coordinates, model)` implements the mathematical representation for the planetary model, `model`.

`[gx gy gz] = gravitysphericalharmonic(planet_coordinates, degree)` uses the degree and order that `degree` specifies.

`[gx gy gz] = gravitysphericalharmonic(planet_coordinates, model, degree)` uses the degree and order that `degree` specifies. `model` specifies the planetary model.

`[gx gy gz] = gravitysphericalharmonic(planet_coordinates, model, degree, action)` uses the specified `action` when input is out of range.

`[gx gy gz] = gravitysphericalharmonic(planet_coordinates, 'Custom', degree, {datafile dfreader}, action)` implements the mathematical representation for a custom model planet. `datafile` defines the planetary model. `dfreader` specifies the reader for `datafile`.

This function has the following limitations:

- The function excludes the centrifugal effects of planetary rotation, and the effects of a precessing reference frame.
- Spherical harmonic gravity model is valid for radial positions greater than the planet equatorial radius. Minor errors might occur for radial positions near or at the planetary surface. The spherical harmonic gravity model is not valid for radial positions less than planetary surface.

Input Arguments

planet_coordinates

M -by-3 array of Planet-Centered Planet-Fixed coordinates in meters. The z -axis is positive toward the North Pole. If *model* is 'EGM2008' or 'EGM96' (Earth), the planet coordinates are ECEF coordinates.

model

Planetary model. Default is 'EGM2008'. Specify one:

Planetary Model	Planet
'EGM2008'	Earth Gravitational Model 2008. Planet coordinates are ECEF (WGS84).
'EGM96'	Earth Gravitational Model 1996. Planet coordinates are ECEF (WGS84).
'LP100K'	100th degree Moon model.
'LP165P'	165th degree Moon model.
'GMM2B'	Goddard Mars model 2B.
'Custom'	<p>Custom planetary model that you define in <i>datafile</i>.</p> <hr/> <p>Note To deploy a custom planetary model, explicitly include the custom data and reader files to the MATLAB Compiler™ (mcc) command at compilation. For example:</p> <pre>mcc -m mycustomsphericalgravityfunction... -a customDataFile -a customReaderFile</pre> <p>For other planetary models, use the MATLAB Compiler as usual.</p>
'EIGENGL04C'	Combined Earth gravity field model EIGEN-GL04C.

When inputting a large PCPF array and a high degree value, you might receive an out-of-memory error. For more information about avoiding out-of-memory errors in the MATLAB environment, see “Resolve “Out of Memory” Errors”.

When inputting a large PCPF array, you might receive a maximum matrix size limitation. To determine the largest matrix or array that you can create in the MATLAB environment for your platform, see “Performance and Memory”.

degree

Scalar value that specifies the degree and order of the harmonic gravity model.

Planetary Model	Degree and Order
'EGM2008'	<p>Maximum degree and order is 2159.</p> <p>Default degree and order are 120.</p>
'EGM96'	<p>Maximum degree and order is 360.</p> <p>Default degree and order are 70.</p>

Planetary Model	Degree and Order
'LP100K'	Maximum degree and order is 100. Default degree and order are 60.
'LP165P'	Maximum degree and order is 165. Default degree and order are 60.
'GMM2B'	Maximum degree and order is 80. Default degree and order are 60.
'Custom'	Maximum degree is default degree and order.
'EIGENGL04C'	Maximum degree and order is 360. Default degree and order are 70.

When inputting a large PCPF array and a high degree value, you might receive an out-of-memory error. For more information about avoiding out-of-memory errors in the MATLAB environment, see “Performance and Memory”.

When inputting a large PCPF array, you might receive a maximum matrix size limitation. To determine the largest matrix or array that you can create in the MATLAB environment for your platform, see “Performance and Memory”.

action

Action for out-of-range input. Specify one:

'Error'
'Warning' (default)
'None'

'Custom'

Character vector or string that specifies that *datafile* contains definitions for a custom planetary model.

datafile

File that contains definitions for a custom planetary model. For an example of file content, see `aerogmm2b.mat`.

This file must contain the following variables.

Variable	Description
<i>Re</i>	Scalar of planet equatorial radius in meters (m)
<i>GM</i>	Scalar of planetary gravitational parameter in meters cubed per second squared (m^3/s^2)
<i>degree</i>	Scalar of maximum degree
<i>C</i>	$(\text{degree}+1)$ -by- $(\text{degree}+1)$ matrix containing normalized spherical harmonic coefficients matrix, <i>C</i>

Variable	Description
<i>S</i>	(<i>degree</i> +1)-by-(<i>degree</i> +1) matrix containing normalized spherical harmonic coefficients matrix, <i>S</i>

This parameter requires that you specify a program in the *dfreader* parameter to read the data file.

dfreader

Specify a MATLAB function to read *datafile*. The reader file that you specify depends on the file type of *datafile*.

Data File Type	Description
MATLAB file	Specify the MATLAB load function, for example, @load.
Other file type	Specify a custom MATLAB reader function. For examples of custom reader functions, see <i>astReadSHAfile.m</i> and <i>astReadEGMfile.m</i> . Note the output variable order in these files.

Output Arguments

gx

Array of *N* gravity values in the x-axis of the Planet-Centered Planet-Fixed coordinates in meters per second squared (m/s²).

gy

Array of *N* gravity values in the y-axis of the Planet-Centered Planet-Fixed coordinates in meters per second squared (m/s²).

gz

Array of *N* gravity values in the z-axis of the Planet-Centered Planet-Fixed coordinates in meters per second squared (m/s²).

Examples

Calculate the gravity in the x-axis at the equator on the surface of Earth. This example uses the default 120 degree model of EGM2008 with default warning actions:

```
gx = gravitysphericalharmonic( [-6378.1363e3 0 0] )
```

Calculate the gravity at 25000 m over the south pole of Earth. This example uses the 70 degree model of EGM96 with error actions:

```
[gx, gy, gz] = gravitysphericalharmonic( [0 0 -6381.751e3], 'EGM96', 'Error' )
```

Calculate the gravity at 15000 m over the equator and 11000 m over the North Pole. This example uses a 30th order GMM2B Mars model with warning actions:

```
p = [2412.648e3 -2412.648e3 0; 0 0 3397.2e3]
[gx, gy, gz] = gravitysphericalharmonic( p, 'GMM2B', 30, 'Warning' )
```

Calculate the gravity at 15000 m over the equator and 11000 m over the North Pole. This example uses a 60th degree custom planetary model with no actions:

```
p = [2412.648e3 -2412.648e3 0; 0 0 3397e3]
[gx, gy, gz] = gravitysphericalharmonic( p, 'custom', 60, ...
{'GMM2BC80_SHA.txt' @astReadSHAFile}, 'None' )
```

Calculate the gravity at 25000 meters over the south pole of Earth using a 120th order EIGEN-GL04C Earth model with warning actions:

```
p = [0 0 -6381.751e3]
[gx, gy, gz] = gravitysphericalharmonic( p, 'EIGENGL04C', ...
120, 'Warning' )
```

Tips

- When inputting a large PCPF array and a high degree value, you might receive an out-of-memory error. For more information about avoiding out-of-memory errors in the MATLAB environment, see “Performance and Memory”.
- When inputting a large PCPF array, you might receive a maximum matrix size limitation. To determine the largest matrix or array that you can create in the MATLAB environment for your platform, see “Performance and Memory”.

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See Also

geoidegm96 | gravitycentrifugal | gravitywgs84 | gravityzonal

Introduced in R2010a

gravitywgs84

Implement 1984 World Geodetic System (WGS84) representation of Earth gravity

Syntax

```
g = gravitywgs84(h, lat)
g = gravitywgs84(h, lat, lon, method, [noatm, nocent, prec, jd], action)
gn = gravitywgs84(h, lat, lon, 'Exact', [noatm, nocent, prec, jd], action)
[gn gt] = gravitywgs84(h, lat, lon, 'Exact', noatm, nocent, prec, jd, action)
```

Description

`g = gravitywgs84(h, lat)` implements the mathematical representation of the geocentric equipotential ellipsoid of WGS84 using altitude `h` and geodetic latitude `lat`.

`g = gravitywgs84(h, lat, lon, method, [noatm, nocent, prec, jd], action)` uses both latitude and longitude, as well as other optional inputs. `method` must be `'CloseApprox'`, `'Exact'`, or `TaylorSeries`.

`gn = gravitywgs84(h, lat, lon, 'Exact', [noatm, nocent, prec, jd], action)` calculates an array of total gravity values in the direction normal to the Earth surface.

`[gn gt] = gravitywgs84(h, lat, lon, 'Exact', noatm, nocent, prec, jd, action)` calculates gravity values in the direction both normal and tangential to the Earth surface.

Examples

Normal Gravity with Taylor Series

Calculate the normal gravity at 5000 meters and 55 degrees latitude using the Taylor Series approximation method and return errors for out-of-range inputs:

```
g = gravitywgs84(5000, 55, 'TaylorSeries', 'Error')
g =
    9.7997
```

Normal Gravity with Close Approximation

Calculate the normal gravity at 15,000 meters, 45 degrees latitude, and 120 degrees longitude using the Close Approximation method with atmosphere, centrifugal effects, and no precession. A warning, enabled by default, is returned for out-of-range inputs.

```
g = gravitywgs84(15000, 45, 120, 'CloseApprox')
```

```
g =
    9.7601
```

Normal and Tangential Gravity

Calculate the normal and tangential gravity at 1000 meters, 0 degrees latitude, and 20 degrees longitude using the Exact method with atmosphere, centrifugal effects, and no precession. A warning, enabled by default, is returned for out-of-range inputs.

```
[gn, gt] = gravitywgs84(1000,0,20,'Exact')
gn =
    9.7772
gt =
    0
```

Normal and Tangential Gravity with Latitude, Longitude, and Exact Method

Calculate the normal and tangential gravity at 1000 meters, 0 degrees latitude, and 20 degrees longitude, and the normal and tangential gravity at 11,000 meters, 30 degrees latitude, and 50 degrees longitude using the Exact method with atmosphere, centrifugal effects, and no precession. Do not return actions for out-of-range inputs.

```
h = [1000; 11000];
lat = [0; 30];
lon = [20; 50];
[gn, gt] = gravitywgs84(h,lat,lon,'Exact','None')
gn =
    9.7772
    9.7594
gt =
    1.0e-04 *
         0
    -0.7751
```

Normal Gravity with Latitude, Longitude, and Close Approximation Method

Calculate the normal gravity at 15,000 meters, 45 degrees latitude, and 120 degrees longitude, and the normal gravity at 5000 meters, 55 degrees latitude, and 100 degrees longitude using the Close Approximation method with atmosphere, no centrifugal effects, and no precession. A warning, enabled by default, is returned for out-of-range inputs.

```
h = [15000 5000];
lat = [45 55];
lon = [120 100];
g = gravitywgs84(h,lat,lon,'CloseApprox',[false true false 0])
```

```
g =  
    9.7771    9.8109
```

Normal and Tangential Gravity with Latitude, Longitude, Julian date, and Exact Method

Calculate the normal and tangential gravity at 1000 meters, 0 degrees latitude, and 20 degrees longitude using the Exact method with atmosphere, centrifugal effects, and precession at Julian date 2451545. Return warnings for out-of-range inputs.

```
[gn, gt] = gravitywgs84(1000,0,20,'Exact', ...  
    [false false true 2451545],'Warning')
```

```
gn =  
    9.7772
```

```
gt =  
    0
```

Normal Gravity with Julian Date, No Atmosphere, and Close Method

Calculate the normal gravity at 15,000 meters, 45 degrees latitude, and 120 degrees longitude using the Close Approximation method with no atmosphere, with centrifugal effects, and with precession at Julian date 2451545. Return errors for out-of-range inputs.

```
g = gravitywgs84(15000,45,120,'CloseApprox', ...  
    [true false true 2451545],'Error')
```

```
g =  
    9.7601
```

Normal Gravity with Julian Date, No Atmosphere, and Exact Method

Calculate the total normal gravity at 15,000 meters, 45 degrees latitude, and 120 degrees longitude using the Exact method with no atmosphere, with centrifugal effects, and with precession at Julian date 2451545. Return errors for out-of-range inputs.

```
gn = gravitywgs84(15000,45,120,'Exact', ...  
    [true false true 2451545],'Error')
```

```
gn =  
    9.7601
```

Input Arguments

h — Altitudes

array

Altitudes, specified as an array of m values, with respect to the WGS84 ellipsoid, in meters.

Data Types: `double`

lat — Geodetic latitudes

array

Geodetic latitudes, specified as an array of m latitudes in degrees, where the north latitude is positive, and south latitude is negative.

Data Types: `double`

lon — Geodetic longitudes

array

Geodetic longitudes, specified as an array of m longitudes, in degrees, where the east longitude is positive, and west longitude is negative.

Only use this input when you specify `method` as `'CloseApprox'` or `'Exact'`.

Data Types: `double`

method — Gravity calculation method

`'TaylorSeries'` (default) | `'CloseApprox'` | `'Exact'`

Gravity calculation method, specified as:

- `'TaylorSeries'` — Medium gravity precision
- `'CloseApprox'` — Close gravity precision
- `'Exact'` — Exact gravity precision

For more information, see “Limitations” on page 4-427.

Data Types: `double`

noatm — Earth atmosphere

`false` (default) | `true`

Exclude or include Earth atmosphere, specified as `true` or `false`:

- `false` — Include the mass of the atmosphere in the value for the Earth gravitational field.
- `true` — Exclude the mass of the atmosphere in the value for the Earth gravitational field.

Only use this input when you specify `method` as `'CloseApprox'` or `'Exact'`.

Data Types: `logical`

nocent — Atmosphere

`false` (default) | `true`

Remove or include centrifugal effects, specified as:

- `false` — Calculate gravity including the centrifugal force resulting from the Earth angular velocity; the centrifugal contribution is included.
- `true` — Calculate gravity based on pure attraction resulting from the normal gravitational potential; the centrifugal contribution is excluded.

Only use this input when you specify method as 'CloseApprox' or 'Exact'.

Data Types: `logical`

prec — Atmosphere

`false` (default) | `true`

Include or exclude a precession reference frame.

- `false` — Calculate gravity using the angular velocity of the Earth as the value of the standard Earth rotating at a constant angular velocity.
- `true` — Calculate gravity using the International Astronomical Union (IAU) value of the Earth angular velocity and the precession rate in right ascension. For the precession rate in right ascension, this option calculates Julian centuries from Epoch J2000.0 using the Julian date, `jd`.

Only use this input when you specify method as 'CloseApprox' or 'Exact'.

Data Types: `logical`

jd — Julian date

0 (default) | `scalar`

Julian date, specified as a scalar, to calculate Julian centuries from Epoch J2000.0. The `prec` option uses this option to calculate Julian centuries from Epoch J2000.0 for the precession rate in right ascension.

Only use this input when you specify method as 'CloseApprox' or 'Exact'.

Data Types: `double`

action — Action

'Warning' (default) | 'Error' | 'None'

Action for out-of-range input, specified as:

- `Warning` — Displays warning and indicates that the input is out-of-range.
- `Error` — Displays error and indicates that the input is out-of-range.
- `None` — Does not display warning or error.

Data Types: `char` | `string`

Output Arguments

g — Gravity values normal to Earth surface at specific longitude and latitude

`array`

Gravity values normal to the Earth surface at specific longitude and latitude, returned as an array of *m* gravity values in the direction normal to the Earth surface. A positive value indicates a downward direction.

gn — Total gravity values normal to Earth surface

`array`

Total gravity values normal to the Earth surface at a specific `lat` `lon` location, returned as an array of *m* gravity values. A positive value indicates a downward direction.

Dependencies

This output is available only with method specified as 'Exact'. When method is 'TaylorSeries' or 'CloseApprox', the function assumes that g_n equals g .

gt — Gravity values tangential to Earth surface

array

An array of m gravity values in the direction tangential to the Earth surface at a specific lat lon location. A positive value indicates a northward direction.

Dependencies

This output is available only with method specified as 'Exact'.

Limitations

- The WGS84 gravity calculations are based on the assumption of a geocentric equipotential ellipsoid of revolution. Since the gravity potential is assumed to be the same everywhere on the ellipsoid, there must be a specific theoretical gravity potential that can be uniquely determined from the four independent constants defining the ellipsoid.
- Limit use of the WGS84 Taylor Series model to low geodetic heights. It is sufficient near the surface when submicrogal precision is not necessary. At medium and high geodetic heights, it is less accurate.
- Limit use of the WGS84 Close Approximation model to a geodetic height of 20,000.0 meters (approximately 65,620.0 feet). Below this height, the function gives results with submicrogal precision.
- To predict and determine a satellite orbit with high accuracy, instead of the `gravitywgs84` function, use the `gravitysphericalharmonics` function with the EGM96 option and degree and order 70.

References

- [1] National Imagery and Mapping Agency (NIMA). "Department of Defense World Geodetic System 1984: Its Definition, and Relationship with Local Geodetic Systems, TR8350.2, Third Ed." Department of Defense, Washington, DC: 1997.

See Also

Introduced in R2006b

gravityzonal

Implement zonal harmonic representation of planetary gravity

Syntax

```
[gravityXcoord gravityYcoord, gravityZcoord] = gravityzonal(planetCoord)
[gravityXcoord gravityYcoord, gravityZcoord] = gravityzonal(planetCoord,
degreeGravityModel)
[gravityXcoord gravityYcoord, gravityZcoord] = gravityzonal(planetCoord,
planetModel)
[gravityXcoord gravityYcoord, gravityZcoord] = gravityzonal(planetCoord,
planetModel, degreeGravityModel)
[gravityXcoord gravityYcoord, gravityZcoord] = gravityzonal(planetCoord,
planetModel, degreeGravityModel, action)
[gravityXcoord gravityYcoord, gravityZcoord] = gravityzonal(planetCoord,
'Custom', equatorialRadius, planetaryGravitational, zonalHarmonicCoeff, action)
```

Description

[gravityXcoord gravityYcoord, gravityZcoord] = gravityzonal(planetCoord) implements the mathematical representation of zonal harmonic planetary gravity based on planetary gravitational potential. For input, it takes an m-by-3 matrix that contains planet-centered planet-fixed coordinates from the center of the planet in meters. This function calculates the arrays of m gravity values in the x-, y-, and z-axes of the planet-centered planet-fixed coordinates. It uses the fourth order zonal coefficients for Earth by default.

[gravityXcoord gravityYcoord, gravityZcoord] = gravityzonal(planetCoord, degreeGravityModel) uses the degree of harmonic model.

[gravityXcoord gravityYcoord, gravityZcoord] = gravityzonal(planetCoord, planetModel) uses the planetary model.

[gravityXcoord gravityYcoord, gravityZcoord] = gravityzonal(planetCoord, planetModel, degreeGravityModel) uses the degree of harmonic model and planetary model.

[gravityXcoord gravityYcoord, gravityZcoord] = gravityzonal(planetCoord, planetModel, degreeGravityModel, action) specifies the action for out-of-range input.

[gravityXcoord gravityYcoord, gravityZcoord] = gravityzonal(planetCoord, 'Custom', equatorialRadius, planetaryGravitational, zonalHarmonicCoeff, action) uses the equatorial radius, planetary gravitational parameter, and zonal harmonic coefficients for the custom planetary model.

This function does not include the potential due planet rotation, which excludes the centrifugal effects of planetary rotation and the effects of a precessing reference frame.

Input Arguments

planetCoord

m-by-3 matrix that contains planet-centered planet-fixed coordinates from the center of the planet in meters. If planetModel has a value of 'Earth', this matrix contains Earth-centered Earth-fixed (ECEF) coordinates.

planetModel

Planetary model. Enter one:

- 'Mercury'
- 'Venus'
- 'Earth'
- 'Moon'
- 'Mars'
- 'Jupiter'
- 'Saturn'
- 'Uranus'
- 'Neptune'
- 'Custom'

'Custom' requires you to specify your own planetary model using the equatorialRadius, planetaryGravitational, and zonalHarmonicCoeff parameters.

Default: 'Earth'

degreeGravityModel

Degree of harmonic model.

- 2 — Second degree, J2. Most significant or largest spherical harmonic term, which accounts for the oblateness of a planet. 2 is default if planetModel is 'Mercury', 'Venus', 'Moon', 'Uranus', or 'Neptune'.
- 3 — Third degree, J3. 3 is default if planetModel is 'Mars'.
- 4 — Fourth degree, J4 (default). Default is 4 if planetModel is 'Earth', 'Jupiter', 'Saturn' or 'Custom'.

Default:

equatorialRadius

Planetary equatorial radius in meters. Use this parameter only if you specify planetModel as 'Custom'.

planetaryGravitational

Planetary gravitational parameter in meters cubed per second squared. Use this parameter only if you specify planetModel as 'Custom'.

zonalHarmonicCoeff

3-element array defining the zonal harmonic coefficients that the function uses to calculate zonal harmonics planetary gravity. Use this parameter only if you specify `planetModel` as 'Custom'.

action

Action for out-of-range input. Specify one:

'Error'

'Warning'

'None' (default)

Output Arguments**gravityXcoord**

Array of *m* gravity values in the *x*-axis of the planet-centered planet-fixed coordinates in meters per second squared.

Default:**gravityYcoord**

Array of *m* gravity values in the *y*-axis of the planet-centered planet-fixed coordinates in meters per second squared.

Default:**gravityZcoord**

Array of *m* gravity values in the *z*-axis of the planet-centered planet-fixed coordinates in meters per second squared.

Default:**Examples**

Calculate the gravity in the *x*-axis at the equator on the surface of Earth using the fourth degree model with no warning actions:

```
gx = gravityzonal( [-6378.1363e3 0 0] )
```

```
gx =
```

```
9.8142
```

Calculate the gravity using the close approximation method at 100 m over the geographic South Pole of Earth with error actions:

```
[gx, gy, gz] = gravityzonal( [0 0 -6356.851e3], 'Error' )
```

```
gx =
```

```
0
```

```
gy =
```

```
    0
```

```
gz =
```

```
    9.8317
```

Calculate the gravity at 15000 m over the equator and 11000 m over the geographic North Pole using a second order Mars model with warning actions:

```
p = [2412.648e3 -2412.648e3 0; 0 0 3376.2e3]
[gx, gy, gz] = gravityzonal( p, 'Mars', 2, 'Warning' )
p =
```

```
    2412648    -2412648         0
         0         0    3376200
```

```
gx =
```

```
   -2.6224
         0
```

```
gy =
```

```
    2.6224
         0
```

```
gz =
```

```
         0
   -3.7542
```

Calculate the gravity at 15000 m over the equator and 11000 m over the geographic North Pole using a custom planetary model with no actions:

```
p= [2412.648e3 -2412.648e3 0; 0 0 3376e3]
GM   = 42828.371901e9 % m^3/s^2
Re   = 3397e3 % m
Jvalues = [1.95545367944545e-3 3.14498094262035e-5 ...
-1.53773961526397e-5]
[gx, gy, gz] = gravityzonal( p, 'custom', Re, GM, ...
Jvalues, 'None' )
```

Algorithms

gravityzonal is implemented using the following planetary parameter values for each planet:

Planet	Equatorial Radius (Re) in Meters	Gravitational Parameter (GM) in m ³ /s ²	Zonal Harmonic Coefficients (J Values)
Earth	6378.1363e3	3.986004415e14	[0.0010826269 -0.0000025323 -0.0000016204]
Jupiter	71492.e3	1.268e17	[0.01475 0 -0.00058]
Mars	3397.2e3	4.305e13	[0.001964 0.000036]

Planet	Equatorial Radius (Re) in Meters	Gravitational Parameter (GM) in m ³ /s ²	Zonal Harmonic Coefficients (J Values)
Mercury	2439.0e3	2.2032e13	0.00006
Moon	1738.0e3	4902.799e9	0.0002027
Neptune	24764e3	6.809e15	0.004
Saturn	60268.e3	3.794e16	[0.01645 0 -0.001]
Uranus	25559.e3	5.794e15	0.012
Venus	6052.0e3	3.257e14	0.000027

Alternatives

Zonal Harmonic Gravity Model block

References

Vallado, D. A., *Fundamentals of Astrodynamics and Applications*, McGraw-Hill, New York, 1997.

Fortescue, P., J. Stark, G. Swinerd, (Eds.). *Spacecraft Systems Engineering*, Third Edition, Wiley & Sons, West Sussex, 2003.

Tewari, A., *Atmospheric and Space Flight Dynamics Modeling and Simulation with MATLAB and Simulink*, Birkhäuser, Boston, 2007.

See Also

geoidegm96 | gravitywgs84

Introduced in R2009b

greenwichsrt

Greenwich mean and apparent sidereal times

Note greenwichsrt is not recommended. For replacement functionality, see the `siderealTime` function.

Syntax

```
[thGMST, thGAST] = greenwichSRT(utcJD)
[thGMST, thGAST] = greenwichSRT(utcJD, dUT1, dAT)
```

Description

`[thGMST, thGAST] = greenwichSRT(utcJD)` calculates Greenwich mean and apparent sidereal times at a specific Universal Coordinated Time (UTC). Mean sidereal time accounts only for secular motion (precession). Apparent sidereal time includes secular and periodic contributions.

`[thGMST, thGAST] = greenwichSRT(utcJD, dUT1, dAT)` calculates Greenwich mean and apparent sidereal times at a higher precision using Earth orientation parameters.

Examples

Calculate Greenwich Sidereal Times

Calculate Greenwich sidereal times at 12:00 on January 4, 2019.

```
jd = juliandate([2019 1 4 12 0 0]);
[thGMST, thGAST] = greenwichSRT(jd)
```

```
thGMST =
    283.8103
```

```
thGAST =
    283.8065
```

Input Arguments

utcJD — UTC as Julian date

scalar

Universal Coordinated Time (UTC) as a Julian date, specified as a scalar.

Tip To calculate the Julian date for a particular date, use the `juliandate` function.

Data Types: double

dUT1 – Difference between CUT and UT1 0 (default) | scalar

Difference between the Coordinated Universal Time (UTC) and Universal Time (UT1), specified as a scalar, in seconds.

dAT – Difference between TAI and UTC 0 (default) | scalar

Difference between International Atomic Time (TAI) and Coordinated Universal Time (UTC), specified as a scalar, in seconds.

Output Arguments**thGMST – Greenwich mean sidereal time**

scalar

Greenwich mean sidereal time, specified as a scalar, in seconds.

thGAST – Greenwich apparent sidereal time

scalar

Greenwich apparent sidereal time, specified as a scalar, in seconds.

Limitations

This function requires the Mapping Toolbox license.

References

[1] Vallado, D. A. *Fundamentals of Astrodynamics and Applications*. alg. 1 and eqs. 1-63. New York: McGraw-Hill, 1997.

See Also

CubeSat Vehicle | dcmece2ecef | ecef2eci | eci2ecef

Introduced in R2019a

groundStation

Add ground station to satellite scenario

Syntax

```
groundStation(scenario)
groundStation(scenario, lat, lon)
groundStation( ____, Name, Value)
gs = groundStation( ____ )
```

Description

`groundStation(scenario)` adds a default `GroundStation` object to the specified satellite scenario.

`groundStation(scenario, lat, lon)` sets the Latitude and Longitude properties of the ground station to `lat` and `lon`, respectively. `lat` and `lon` must be of the same length. This length specifies the number of ground stations that the function adds to the input scenario. Together, `lat` and `lon` indicate the locations of the ground stations.

`groundStation(____, Name, Value)` sets options using one or more name-value arguments in addition to any input argument combination from previous syntaxes. For example, `'MinElevationAngle', 10` specifies a minimum elevation angle of 10 degrees.

`gs = groundStation(____)` returns a vector of handles to the added ground stations. Specify any input argument combination from previous syntaxes.

Examples

Add Ground stations to Scenario and Visualize Access Intervals

Create satellite scenario and add ground stations from latitudes and longitudes.

```
startTime = datetime(2020, 5, 1, 11, 36, 0);
stopTime = startTime + days(1);
sampleTime = 60;
sc = satelliteScenario(startTime, stopTime, sampleTime);
lat = [10];
lon = [-30];
gs = groundStation(sc, lat, lon);
```

Add satellites using Keplerian elements.

```
semiMajorAxis = 10000000;
eccentricity = 0;
inclination = 10;
rightAscensionOfAscendingNode = 0;
argumentOfPeriapsis = 0;
trueAnomaly = 0;
sat = satellite(sc, semiMajorAxis, eccentricity, inclination, ...
    rightAscensionOfAscendingNode, argumentOfPeriapsis, trueAnomaly);
```

Add access analysis to the scenario and obtain the table of intervals of access between the satellite and the ground station.

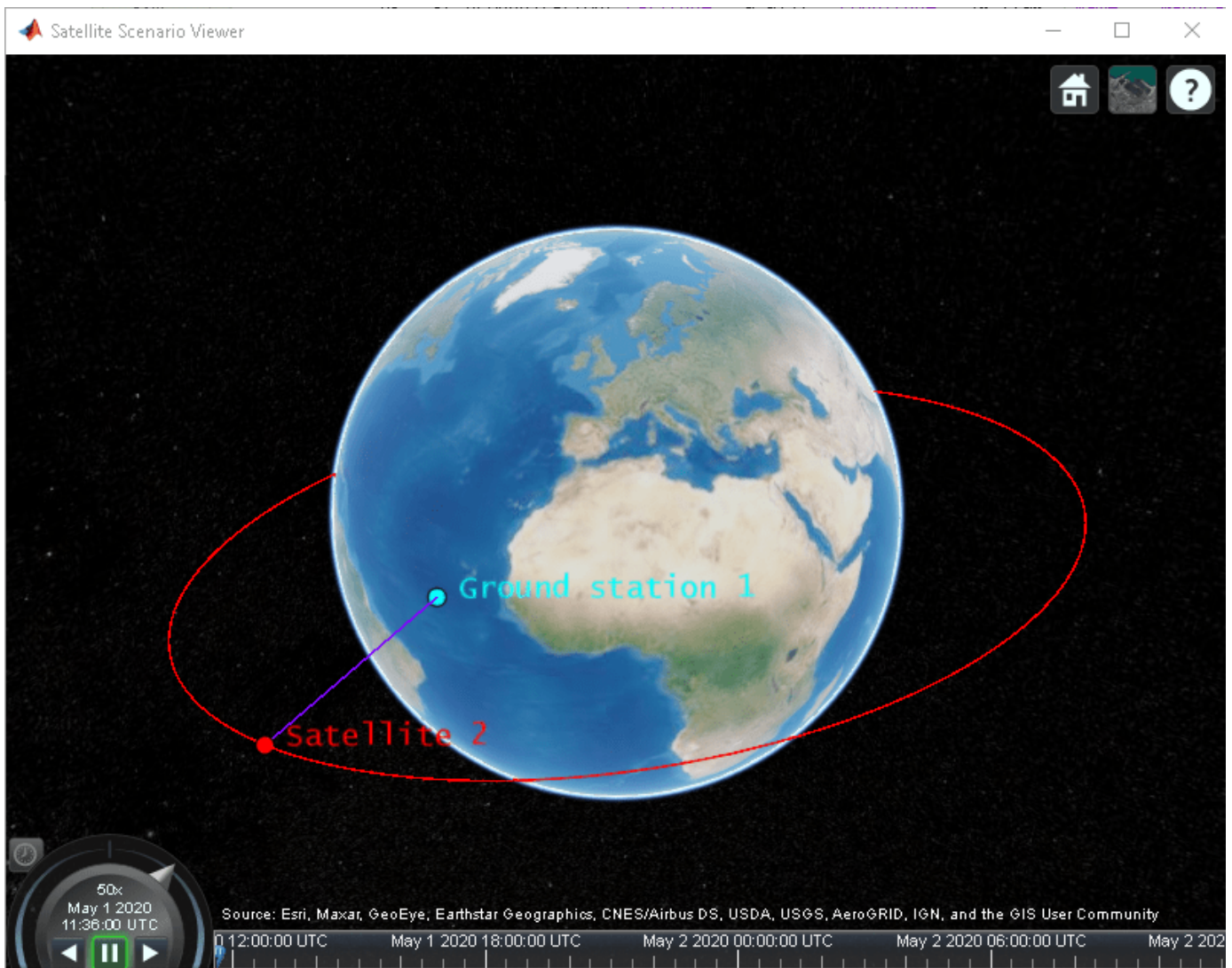
```
ac = access(sat, gs);  
intvls = accessIntervals(ac)
```

```
intvls=8x8 table  
Source
```

Source	Target	IntervalNumber	StartTime	EndTime
"Satellite 2"	"Ground station 1"	1	01-May-2020 11:36:00	01-May-2020
"Satellite 2"	"Ground station 1"	2	01-May-2020 14:20:00	01-May-2020
"Satellite 2"	"Ground station 1"	3	01-May-2020 17:27:00	01-May-2020
"Satellite 2"	"Ground station 1"	4	01-May-2020 20:34:00	01-May-2020
"Satellite 2"	"Ground station 1"	5	01-May-2020 23:41:00	02-May-2020
"Satellite 2"	"Ground station 1"	6	02-May-2020 02:50:00	02-May-2020
"Satellite 2"	"Ground station 1"	7	02-May-2020 05:59:00	02-May-2020
"Satellite 2"	"Ground station 1"	8	02-May-2020 09:06:00	02-May-2020

Play the scenario to visualize the ground stations.

```
play(sc)
```



Input Arguments

scenario – Satellite scenario

satelliteScenario object

Satellite scenario, specified as a satelliteScenario object.

lat, lon – Latitude and longitude

real-valued scalar | real-valued vector

Latitude and longitude of the ground station, specified as a real-valued scalar or real-valued vector.

Name-Value Pair Arguments

Specify optional comma-separated pairs of Name, Value arguments. Name is the argument name and Value is the corresponding value. Name must appear inside quotes. You can specify several name and value pair arguments in any order as Name1, Value1, ..., NameN, ValueN.

Example: 'MinElevationAngle',10 specifies a minimum elevation angle of 10 degrees.

Viewer — Satellite scenario viewer

(default) | row vector of all viewer objects | row vector of `satelliteScenarioViewer` objects

Satellite scenario viewer, specified as a row vector of `satelliteScenarioViewer` objects.

Data Types: `char` | `string`

Name — groundStation name

"groundStation *idx*" (default) | string scalar | string vector | character vector | cell array of character vectors

You can set this property only when calling `groundStation`. After you call `groundStation`, this property is read-only.

groundStation name, specified as a comma-separated pair consisting of 'Name' and a string scalar, string vector, character vector or a cell array of character vectors.

- If only one groundStation is added, specify Name as a string scalar or a character vector.
- If multiple groundStations are added, specify Name as a string vector or a cell array of character vectors. The number of elements in the string vector or cell array must be equal to the number of satellites being added.

In the default value, *idx* is the count of the groundStation added by the `groundStation` object function. If another groundStation of the same name exists, a suffix *idx₂* is added, where *idx₂* is an integer that is incremented by 1 starting from 1 until the name duplication is resolved.

Data Types: `char` | `string`

Latitude — Geodetic latitude of ground stations

42.3001 (default) | scalar | row vector

You can set this property only when calling `groundStation`. After you call `groundStation`, this property is read-only.

Geodetic latitude of ground stations, specified as a scalar. Values must be in the range [-90, 90].

- If you add only one ground station, specify Latitude as a scalar double.
- If you add multiple ground stations, specify Latitude as a vector double whose length is equal to the number of ground stations being added.

When latitude and longitude are specified as `lat`, `lon` inputs to `groundStation`, Latitude specified as a name-value argument takes precedence.

Data Types: `double`

Longitude — Geodetic longitude of ground stations

-71.3504 (default) | scalar | row vector

You can set this property only when calling `groundStation`. After you call `groundStation`, this property is read-only.

Geodetic longitude of ground stations, specified as a scalar or a vector. Values must be in the range [-180, 180].

- If you add only one ground station, specify longitude as a scalar.
- If you add multiple ground stations, specify longitude as a vector whose length is equal to the number of ground stations being added.

When longitude and longitude are specified as `lat`, `lon` inputs to `groundStation`, longitude specified as a name-value argument takes precedence.

Data Types: `double`

Altitude — Altitude of ground station

0 m (default) | scalar | vector

You can set this property only when calling `groundStation`. After you call `groundStation`, this property is read-only.

Altitude of ground stations, specified as a scalar or a vector.

- If you specify `Altitude` as a scalar, the value is assigned to each ground station in the `groundStation`.
- If you specify `Altitude` as a vector, the vector length must be equal to the number of ground stations in the `groundStation`.

When latitude and longitude are specified as `lat`, `lon` inputs to `groundStation`, `Latitude` specified as a name-value argument takes precedence.

Data Types: `double`

MinElevationAngle — Minimum elevation angle

0 (default) | scalar | vector

Minimum elevation angle of a satellite for the satellite to be visible from the ground station, specified as a scalar or row vector. Values must be in the range $[-90, 90]$. For access and link closure to be possible, the elevation angle must be at least equal to the value specified in `MinElevationAngle`.

- If you specify `MinElevationAngle` as a scalar, the value is assigned to each ground station in the `groundStation`.
- If you specify `MinElevationAngle` as a vector, the vector length must be equal to the number of ground stations in the `groundStation`.

Data Types: `double`

Output Arguments

gs — Ground station in scenario

`GroundStation` object

Ground station in the scenario, returned as a `GroundStation` object belonging to the satellite scenario specified by the input `scenario`.

You can modify the `GroundStation` object by changing its property values. The name-value arguments used when calling this function correspond to property names.

See Also

Objects

satelliteScenario | satelliteScenarioViewer

Functions

access | hide | play | satellite | show

Topics

“Satellite Scenario Key Concepts” on page 2-61

Introduced in R2021a

GroundStation

Ground station object belonging to satellite scenario

Description

The GroundStation object defines a ground station object belonging to a satellite scenario.

Creation

You can create GroundStation object using the groundStation object function of the satelliteScenario object.

Properties

Name — GroundStation name

"GroundStation *idx*" (default) | string scalar | string vector | character vector | cell array of character vectors

You can set this property only when calling GroundStation. After you call GroundStation, this property is read-only.

GroundStation name, specified as a comma-separated pair consisting of 'Name' and a string scalar, string vector, character vector or a cell array of character vectors.

- If only one GroundStation is added, specify Name as a string scalar or a character vector.
- If multiple GroundStations are added, specify Name as a string vector or a cell array of character vectors. The number of elements in the string vector or cell array must be equal to the number of satellites being added.

In the default value, *idx* is the count of the GroundStation added by the GroundStation object function. If another GroundStation of the same name exists, a suffix *idx₂* is added, where *idx₂* is an integer that is incremented by 1 starting from 1 until the name duplication is resolved.

Data Types: char | string

ID — GroundStation ID assigned by simulator

real positive scalar

This property is set internally by the simulator and is read-only.

GroundStation ID assigned by the simulator, specified as a positive scalar.

Latitude — Geodetic latitude of ground stations

42.3001 (default) | scalar | row vector

You can set this property only when calling GroundStation. After you call GroundStation, this property is read-only.

Geodetic latitude of ground stations, specified as a scalar. Values must be in the range [-90, 90].

- If you add only one ground station, specify Latitude as a scalar double.
- If you add multiple ground stations, specify Latitude as a vector double whose length is equal to the number of ground stations being added.

When latitude and longitude are specified as `lat`, `lon` inputs to `GroundStation`, Latitude specified as a name-value argument takes precedence.

Data Types: `double`

Longitude — Geodetic longitude of ground stations

-71.3504 (default) | scalar | row vector

You can set this property only when calling `GroundStation`. After you call `GroundStation`, this property is read-only.

Geodetic longitude of ground stations, specified as a scalar or a vector. Values must be in the range [-180, 180].

- If you add only one ground station, specify longitude as a scalar.
- If you add multiple ground stations, specify longitude as a vector whose length is equal to the number of ground stations being added.

When longitude and longitude are specified as `lat`, `lon` inputs to `GroundStation`, longitude specified as a name-value argument takes precedence.

Data Types: `double`

Altitude — Altitude of ground station

0 m (default) | scalar | vector

You can set this property only when calling `GroundStation`. After you call `GroundStation`, this property is read-only.

Altitude of ground stations, specified as a scalar or a vector.

- If you specify `Altitude` as a scalar, the value is assigned to each ground station in the `GroundStation`.
- If you specify `Altitude` as a vector, the vector length must be equal to the number of ground stations in the `GroundStation`.

When latitude and longitude are specified as `lat`, `lon` inputs to `GroundStation`, Latitude specified as a name-value argument takes precedence.

Data Types: `double`

MinElevationAngle — Minimum elevation angle

0 (default) | scalar | vector

Minimum elevation angle of a satellite for the satellite to be visible from the ground station, specified as a scalar or row vector. Values must be in the range [-90, 90]. For access and link closure to be possible, the elevation angle must be at least equal to the value specified in `MinElevationAngle`.

- If you specify `MinElevationAngle` as a scalar, the value is assigned to each ground station in the `GroundStation`.

- If you specify `MinElevationAngle` as a vector, the vector length must be equal to the number of ground stations in the `GroundStation`.

Data Types: `double`

Accesses — Access analysis objects

row vector of `Access` objects

You can set this property only when calling `GroundStation`. After you call `GroundStation`, this property is read-only.

Access analysis objects, specified as a row vector of `Access` objects.

ConicalSensors — Conical sensors

row vector of conical sensors

You can set this property only when calling `conicalSensor`. After you call `conicalSensor`, this property is read-only.

Conical sensors attached to the `GroundStation`, specified as a row vector of conical sensors.

Gimbals — Gimbals

row vector of `Gimbal` objects

You can set this property only when calling `gimbal`. After you call `gimbal`, this property is read-only.

Gimbals attached to the `GroundStation`, specified as the comma-separated pair consisting of `'Gimbals'` and a row vector of `Gimbal` objects.

MarkerColor — Color of marker


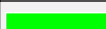

`[1 0 0]` (default) | RGB triplet | string scalar of color name | character vector of color name






Color of the marker, specified as a comma-separated pair consisting of `'MarkerColor'` and either an RGB triplet or a string or character vector of a color name.

For a custom color, specify an RGB triplet or a hexadecimal color code.


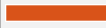

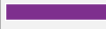

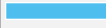

- An RGB triplet is a three-element row vector whose elements specify the intensities of the red, green, and blue components of the color. The intensities must be in the range `[0, 1]`; for example, `[0.4 0.6 0.7]`.
- A hexadecimal color code is a character vector or a string scalar that starts with a hash symbol (`#`) followed by three or six hexadecimal digits, which can range from `0` to `F`. The values are not case sensitive. Thus, the color codes `'#FF8800'`, `'#ff8800'`, `'#F80'`, and `'#f80'` are equivalent.

Alternatively, you can specify some common colors by name. This table lists the named color options, the equivalent RGB triplets, and hexadecimal color codes.

Color Name	Short Name	RGB Triplet	Hexadecimal Color Code	Appearance
<code>'red'</code>	<code>'r'</code>	<code>[1 0 0]</code>	<code>'#FF0000'</code>	
<code>'green'</code>	<code>'g'</code>	<code>[0 1 0]</code>	<code>'#00FF00'</code>	
<code>'blue'</code>	<code>'b'</code>	<code>[0 0 1]</code>	<code>'#0000FF'</code>	

Color Name	Short Name	RGB Triplet	Hexadecimal Color Code	Appearance
'cyan'	'c'	[0 1 1]	'#00FFFF'	
'magenta'	'm'	[1 0 1]	'#FF00FF'	
'yellow'	'y'	[1 1 0]	'#FFFF00'	
'black'	'k'	[0 0 0]	'#000000'	
'white'	'w'	[1 1 1]	'#FFFFFF'	
'none'	Not applicable	Not applicable	Not applicable	No color

Here are the RGB triplets and hexadecimal color codes for the default colors MATLAB uses in many types of plots.

RGB Triplet	Hexadecimal Color Code	Appearance
[0 0.4470 0.7410]	'#0072BD'	
[0.8500 0.3250 0.0980]	'#D95319'	
[0.9290 0.6940 0.1250]	'#EDB120'	
[0.4940 0.1840 0.5560]	'#7E2F8E'	
[0.4660 0.6740 0.1880]	'#77AC30'	
[0.3010 0.7450 0.9330]	'#4DBEEE'	
[0.6350 0.0780 0.1840]	'#A2142F'	

MarkerSize – Size of marker

10 (default) | positive scalar less than 30

Size of the marker, specified as a comma-separated pair consisting of 'MarkerSize' and a real positive scalar less than 30. The unit is in pixels.

ShowLabel – State of GroundStation label visibility

true or 1 (default) | false or 0

State of GroundStation label visibility, specified as a comma-separated pair consisting of 'ShowLabel' and numerical or logical value of 1 (true) or 0 (false).

Data Types: logical

LabelFontSize – Font size of GroundStation label

15 (default) | positive scalar less than 30

Font size of the GroundStation label, specified as a comma-separated pair consisting of 'LabelFontSize' and a positive scalar less than 30.

LabelFontColor – Font color of GroundStation label

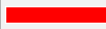



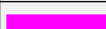
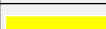


[1,0,0] (default) | RGB triplet | string scalar of color name | character vector of color name

Font color of the GroundStation label, specified as a comma-separated pair consisting of 'LabelFontColor' and either an RGB triplet or a string or character vector of a color name.

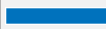






For a custom color, specify an RGB triplet or a hexadecimal color code.

- An RGB triplet is a three-element row vector whose elements specify the intensities of the red, green, and blue components of the color. The intensities must be in the range $[0, 1]$; for example, $[0.4 \ 0.6 \ 0.7]$.
- A hexadecimal color code is a character vector or a string scalar that starts with a hash symbol (#) followed by three or six hexadecimal digits, which can range from 0 to F. The values are not case sensitive. Thus, the color codes '#FF8800', '#ff8800', '#F80', and '#f80' are equivalent.

Alternatively, you can specify some common colors by name. This table lists the named color options, the equivalent RGB triplets, and hexadecimal color codes.

Color Name	Short Name	RGB Triplet	Hexadecimal Color Code	Appearance
'red'	'r'	[1 0 0]	'#FF0000'	
'green'	'g'	[0 1 0]	'#00FF00'	
'blue'	'b'	[0 0 1]	'#0000FF'	
'cyan'	'c'	[0 1 1]	'#00FFFF'	
'magenta'	'm'	[1 0 1]	'#FF00FF'	
'yellow'	'y'	[1 1 0]	'#FFFF00'	
'black'	'k'	[0 0 0]	'#000000'	
'white'	'w'	[1 1 1]	'#FFFFFF'	
'none'	Not applicable	Not applicable	Not applicable	No color

Here are the RGB triplets and hexadecimal color codes for the default colors MATLAB uses in many types of plots.

RGB Triplet	Hexadecimal Color Code	Appearance
[0 0.4470 0.7410]	'#0072BD'	
[0.8500 0.3250 0.0980]	'#D95319'	
[0.9290 0.6940 0.1250]	'#EDB120'	
[0.4940 0.1840 0.5560]	'#7E2F8E'	
[0.4660 0.6740 0.1880]	'#77AC30'	
[0.3010 0.7450 0.9330]	'#4DBEEE'	
[0.6350 0.0780 0.1840]	'#A2142F'	

Object Functions

access	Add access analysis objects to satellite scenario
conicalSensor	Add conical sensor to satellite scenario
gimbal	Add gimbal to satellite or ground station
show	Show object in satellite scenario viewer
aer	Calculate azimuth angle, elevation angle, and range in NED frame from another satellite or ground station
hide	Hides satellite scenario entity from viewer

Examples

Add Ground stations to Scenario and Visualize Access Intervals

Create satellite scenario and add ground stations from latitudes and longitudes.

```
startTime = datetime(2020, 5, 1, 11, 36, 0);
stopTime = startTime + days(1);
sampleTime = 60;
sc = satelliteScenario(startTime, stopTime, sampleTime);
lat = [10];
lon = [-30];
gs = groundStation(sc, lat, lon);
```

Add satellites using Keplerian elements.

```
semiMajorAxis = 10000000;
eccentricity = 0;
inclination = 10;
rightAscensionOfAscendingNode = 0;
argumentOfPeriapsis = 0;
trueAnomaly = 0;
sat = satellite(sc, semiMajorAxis, eccentricity, inclination, ...
    rightAscensionOfAscendingNode, argumentOfPeriapsis, trueAnomaly);
```

Add access analysis to the scenario and obtain the table of intervals of access between the satellite and the ground station.

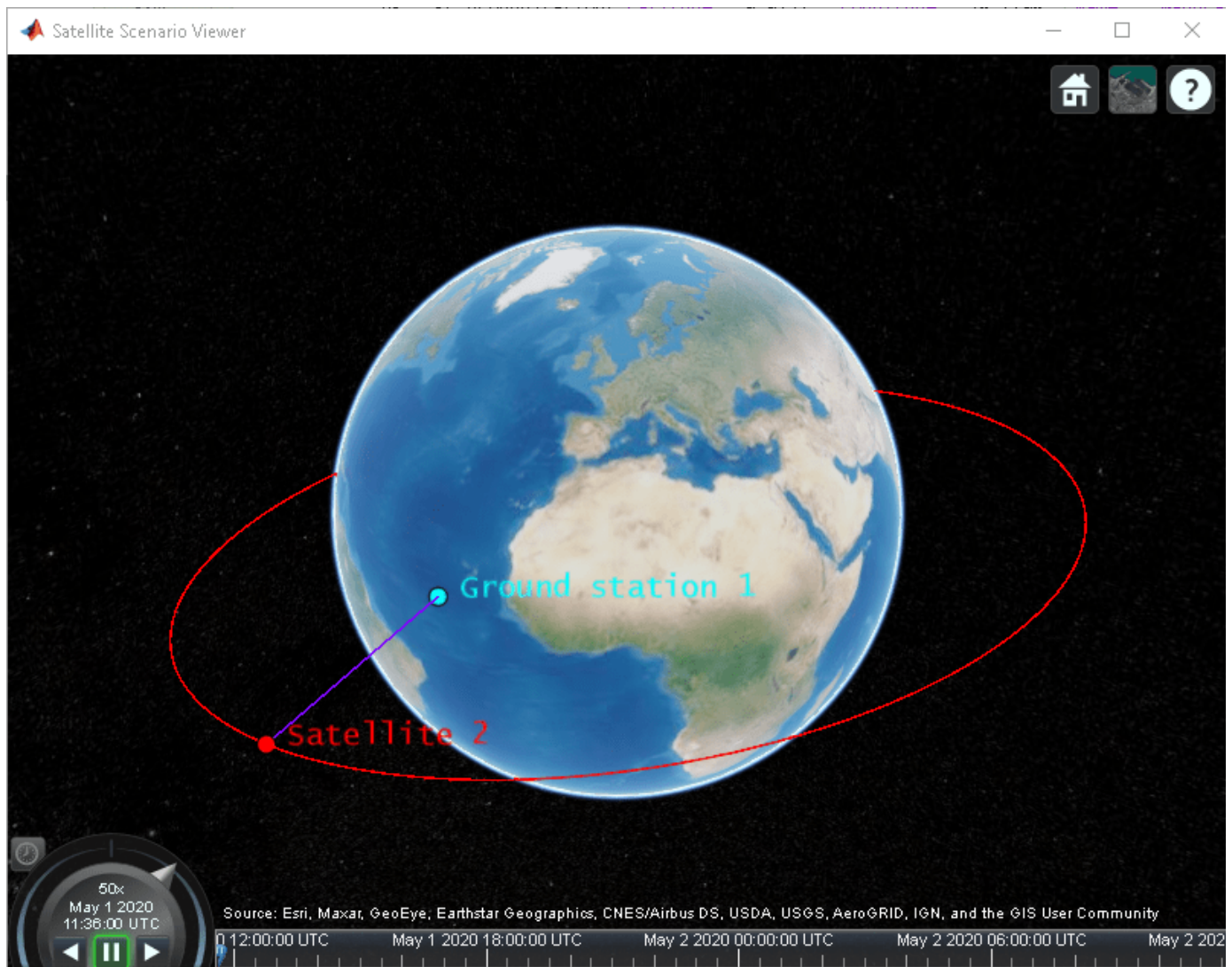
```
ac = access(sat, gs);
intvls = accessIntervals(ac)
```

intvls=8×8 table

Source	Target	IntervalNumber	StartTime	EndTime
"Satellite 2"	"Ground station 1"	1	01-May-2020 11:36:00	01-May-2020
"Satellite 2"	"Ground station 1"	2	01-May-2020 14:20:00	01-May-2020
"Satellite 2"	"Ground station 1"	3	01-May-2020 17:27:00	01-May-2020
"Satellite 2"	"Ground station 1"	4	01-May-2020 20:34:00	01-May-2020
"Satellite 2"	"Ground station 1"	5	01-May-2020 23:41:00	02-May-2020
"Satellite 2"	"Ground station 1"	6	02-May-2020 02:50:00	02-May-2020
"Satellite 2"	"Ground station 1"	7	02-May-2020 05:59:00	02-May-2020
"Satellite 2"	"Ground station 1"	8	02-May-2020 09:06:00	02-May-2020

Play the scenario to visualize the ground stations.

```
play(sc)
```



See Also

Objects

`satelliteScenario` | `satelliteScenarioViewer`

Functions

`access` | `conicalSensor` | `groundStation` | `hide` | `play` | `satellite` | `show`

Topics

“Satellite Scenario Key Concepts” on page 2-61

Introduced in R2021a

groundTrack

Package: satelliteScenario

Add ground track object to satellite in scenario

Syntax

```
groundTrack(sat)
groundTrack( ____, Name, Value)
```

Description

`groundTrack(sat)` adds ground track visualization for each satellite in `sat` based on their current positions. The ground track begins at the scenario `StartTime`, and ends at the `StopTime`. The spacing between samples that make up the ground track visualization is determined by the scenario `SampleTime`. If no viewer is open, a new viewer is launched, and the ground track is displayed. If a viewer is already open, the ground track is added to that viewer. By default, ground tracks will be displayed in 2-D.

`groundTrack(____, Name, Value)` adds a `groundTrack` object by using one or more name-value pairs. Enclose each property name in quotes.

Input Arguments

sat — Satellite

row vector of `Satellite` objects

Satellite, specified as a row vector of `Satellite` objects.

Name-Value Pair Arguments

Specify optional comma-separated pairs of `Name`, `Value` arguments. `Name` is the argument name and `Value` is the corresponding value. `Name` must appear inside quotes. You can specify several name and value pair arguments in any order as `Name1, Value1, ..., NameN, ValueN`.

Example: `'LeadTime', 3600` sets the lead time of the ground track to 3600 seconds upon creation.

Viewer — Viewer on which ground track is visualized

`satelliteScenarioViewer` object

Viewer on which ground track is visualized, specified as a `satelliteScenarioViewer` object.

LeadTime — Period of future ground track to be visualized

`StartTime` to `StopTime` (default) | real positive scalar

Period of future ground track to be visualized in `Viewer`, specified as a comma-separated pair consisting of `'LeadTime'` and a real positive scalar in seconds.

TrailTime — Period of ground track history to be visualized

`StartTime` to `StopTime` (default) | real positive scalar

Period of ground track history to be visualized in Viewer, specified as a comma-separated pair consisting of 'TrailTime' and a real positive scalar in seconds.

LineWidth — Visual width of ground track

1 (default) | scalar

Visual width of ground track in pixels, specified as a comma-separated pair consisting of 'LineWidth' and a scalar in the range (0,10).

The line width cannot be thinner than the width of a pixel. If you set the line width to a value that is less than the width of a pixel on your system, the line displays as one pixel wide.

LeadTime — Period of ground track to be visualized

StartTime to StopTime (default) | positive scalar

Period of the ground track to be visualized in the satellite scenario viewer, specified as a comma-separated pair consisting of 'LeadTime' and a real positive scalar in seconds.

TrailTime — Period of ground track history to be visualized

StartTime to StopTime (default) | positive scalar

Period of the ground track history to be visualized in Viewer, specified as a comma-separated pair consisting of 'TrailTime' and a real positive scalar in seconds.

LineWidth — Visual width of ground track

1 (default) | scalar in the range (0 10]

Visual width of the ground track in pixels, specified as a comma-separated pair consisting of 'LineWidth' and a scalar in the range (0 10].

The line width cannot be thinner than the width of a pixel. If you set the line width to a value that is less than the width of a pixel on your system, the line displays as one pixel wide.

LeadLineColor — Color of future ground track line





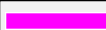
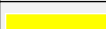


[1 0 1] (default) | RGB triplet | RGB triplet | string scalar of color name | character vector of color name

Color of the future ground track line, specified as a comma-separated pair consisting of 'LeadLineColor' and an RGB triplet, a hexadecimal color code, a color name, or a short name.

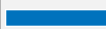






For a custom color, specify an RGB triplet or a hexadecimal color code.

- An RGB triplet is a three-element row vector whose elements specify the intensities of the red, green, and blue components of the color. The intensities must be in the range [0, 1]; for example, [0.4 0.6 0.7].
- A hexadecimal color code is a character vector or a string scalar that starts with a hash symbol (#) followed by three or six hexadecimal digits, which can range from 0 to F. The values are not case sensitive. Thus, the color codes '#FF8800', '#ff8800', '#F80', and '#f80' are equivalent.

Alternatively, you can specify some common colors by name. This table lists the named color options, the equivalent RGB triplets, and hexadecimal color codes.

Color Name	Short Name	RGB Triplet	Hexadecimal Color Code	Appearance
'red'	'r'	[1 0 0]	'#FF0000'	
'green'	'g'	[0 1 0]	'#00FF00'	
'blue'	'b'	[0 0 1]	'#0000FF'	
'cyan'	'c'	[0 1 1]	'#00FFFF'	
'magenta'	'm'	[1 0 1]	'#FF00FF'	
'yellow'	'y'	[1 1 0]	'#FFFF00'	
'black'	'k'	[0 0 0]	'#000000'	
'white'	'w'	[1 1 1]	'#FFFFFF'	
'none'	Not applicable	Not applicable	Not applicable	No color

Here are the RGB triplets and hexadecimal color codes for the default colors MATLAB uses in many types of plots.

RGB Triplet	Hexadecimal Color Code	Appearance
[0 0.4470 0.7410]	'#0072BD'	
[0.8500 0.3250 0.0980]	'#D95319'	
[0.9290 0.6940 0.1250]	'#EDB120'	
[0.4940 0.1840 0.5560]	'#7E2F8E'	
[0.4660 0.6740 0.1880]	'#77AC30'	
[0.3010 0.7450 0.9330]	'#4DBEEE'	
[0.6350 0.0780 0.1840]	'#A2142F'	

Example: 'blue'

Example: [0 0 1]

Example: '#0000FF'

TrailLineColor — Color of ground track line history

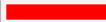







[1 0.5 0] (default) | RGB triplet | RGB triplet | string scalar of color name | character vector of color name

Color of the ground track line history, specified as a comma-separated pair consisting of 'TrailLineColor' and an RGB triplet, a hexadecimal color code, a color name, or a short name.

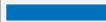





For a custom color, specify an RGB triplet or a hexadecimal color code.

- An RGB triplet is a three-element row vector whose elements specify the intensities of the red, green, and blue components of the color. The intensities must be in the range [0, 1]; for example, [0.4 0.6 0.7].
- A hexadecimal color code is a character vector or a string scalar that starts with a hash symbol (#) followed by three or six hexadecimal digits, which can range from 0 to F. The values are not case sensitive. Thus, the color codes '#FF8800', '#ff8800', '#F80', and '#f80' are equivalent.

Alternatively, you can specify some common colors by name. This table lists the named color options, the equivalent RGB triplets, and hexadecimal color codes.

Color Name	Short Name	RGB Triplet	Hexadecimal Color Code	Appearance
'red'	'r'	[1 0 0]	'#FF0000'	
'green'	'g'	[0 1 0]	'#00FF00'	
'blue'	'b'	[0 0 1]	'#0000FF'	
'cyan'	'c'	[0 1 1]	'#00FFFF'	
'magenta'	'm'	[1 0 1]	'#FF00FF'	
'yellow'	'y'	[1 1 0]	'#FFFF00'	
'black'	'k'	[0 0 0]	'#000000'	
'white'	'w'	[1 1 1]	'#FFFFFF'	
'none'	Not applicable	Not applicable	Not applicable	No color

Here are the RGB triplets and hexadecimal color codes for the default colors MATLAB uses in many types of plots.

RGB Triplet	Hexadecimal Color Code	Appearance
[0 0.4470 0.7410]	'#0072BD'	
[0.8500 0.3250 0.0980]	'#D95319'	
[0.9290 0.6940 0.1250]	'#EDB120'	
[0.4940 0.1840 0.5560]	'#7E2F8E'	
[0.4660 0.6740 0.1880]	'#77AC30'	
[0.3010 0.7450 0.9330]	'#4DBEEE'	
[0.6350 0.0780 0.1840]	'#A2142F'	

Example: 'blue'

Example: [0 0 1]

Example: '#0000FF'

See Also

Objects

satelliteScenario | satelliteScenarioViewer

Functions

access | groundStation | hide | play | satellite | show

Topics

"Satellite Scenario Key Concepts" on page 2-61

Introduced in R2021a

GroundTrack

Ground track object belonging to satellite in scenario

Description

The GroundTrack object defines a ground track object belonging to a satellite in a scenario.

Creation

You can create a GroundTrack object using the groundTrack object function of the Satellite object.

Properties

LeadTime — Period of ground track to be visualized

StartTime to StopTime (default) | positive scalar

Period of the ground track to be visualized in the satellite scenario viewer, specified as a comma-separated pair consisting of 'LeadTime' and a real positive scalar in seconds.

TrailTime — Period of ground track history to be visualized

StartTime to StopTime (default) | positive scalar

Period of the ground track history to be visualized in Viewer, specified as a comma-separated pair consisting of 'TrailTime' and a real positive scalar in seconds.

LineWidth — Visual width of ground track

1 (default) | scalar in the range (0 10]

Visual width of the ground track in pixels, specified as a comma-separated pair consisting of 'LineWidth' and a scalar in the range (0 10].

The line width cannot be thinner than the width of a pixel. If you set the line width to a value that is less than the width of a pixel on your system, the line displays as one pixel wide.

LeadLineColor — Color of future ground track line

[1 0 1] (default) | RGB triplet | RGB triplet | string scalar of color name | character vector of color name

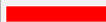



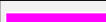
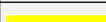


Color of the future ground track line, specified as a comma-separated pair consisting of 'LeadLineColor' and an RGB triplet, a hexadecimal color code, a color name, or a short name.

For a custom color, specify an RGB triplet or a hexadecimal color code.





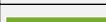


- An RGB triplet is a three-element row vector whose elements specify the intensities of the red, green, and blue components of the color. The intensities must be in the range [0, 1]; for example, [0.4 0.6 0.7].

- A hexadecimal color code is a character vector or a string scalar that starts with a hash symbol (#) followed by three or six hexadecimal digits, which can range from 0 to F. The values are not case sensitive. Thus, the color codes '#FF8800', '#ff8800', '#F80', and '#f80' are equivalent.

Alternatively, you can specify some common colors by name. This table lists the named color options, the equivalent RGB triplets, and hexadecimal color codes.

Color Name	Short Name	RGB Triplet	Hexadecimal Color Code	Appearance
'red'	'r'	[1 0 0]	'#FF0000'	
'green'	'g'	[0 1 0]	'#00FF00'	
'blue'	'b'	[0 0 1]	'#0000FF'	
'cyan'	'c'	[0 1 1]	'#00FFFF'	
'magenta'	'm'	[1 0 1]	'#FF00FF'	
'yellow'	'y'	[1 1 0]	'#FFFF00'	
'black'	'k'	[0 0 0]	'#000000'	
'white'	'w'	[1 1 1]	'#FFFFFF'	
'none'	Not applicable	Not applicable	Not applicable	No color

Here are the RGB triplets and hexadecimal color codes for the default colors MATLAB uses in many types of plots.

RGB Triplet	Hexadecimal Color Code	Appearance
[0 0.4470 0.7410]	'#0072BD'	
[0.8500 0.3250 0.0980]	'#D95319'	
[0.9290 0.6940 0.1250]	'#EDB120'	
[0.4940 0.1840 0.5560]	'#7E2F8E'	
[0.4660 0.6740 0.1880]	'#77AC30'	
[0.3010 0.7450 0.9330]	'#4DBEEE'	
[0.6350 0.0780 0.1840]	'#A2142F'	

Example: 'blue'

Example: [0 0 1]

Example: '#0000FF'

TrailLineColor — Color of ground track line history

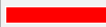







[1 0.5 0] (default) | RGB triplet | RGB triplet | string scalar of color name | character vector of color name

Color of the ground track line history, specified as a comma-separated pair consisting of 'TrailLineColor' and an RGB triplet, a hexadecimal color code, a color name, or a short name.








For a custom color, specify an RGB triplet or a hexadecimal color code.

- An RGB triplet is a three-element row vector whose elements specify the intensities of the red, green, and blue components of the color. The intensities must be in the range $[0, 1]$; for example, $[0.4 \ 0.6 \ 0.7]$.
- A hexadecimal color code is a character vector or a string scalar that starts with a hash symbol (#) followed by three or six hexadecimal digits, which can range from 0 to F. The values are not case sensitive. Thus, the color codes '#FF8800', '#ff8800', '#F80', and '#f80' are equivalent.

Alternatively, you can specify some common colors by name. This table lists the named color options, the equivalent RGB triplets, and hexadecimal color codes.

Color Name	Short Name	RGB Triplet	Hexadecimal Color Code	Appearance
'red'	'r'	[1 0 0]	'#FF0000'	
'green'	'g'	[0 1 0]	'#00FF00'	
'blue'	'b'	[0 0 1]	'#0000FF'	
'cyan'	'c'	[0 1 1]	'#00FFFF'	
'magenta'	'm'	[1 0 1]	'#FF00FF'	
'yellow'	'y'	[1 1 0]	'#FFFF00'	
'black'	'k'	[0 0 0]	'#000000'	
'white'	'w'	[1 1 1]	'#FFFFFF'	
'none'	Not applicable	Not applicable	Not applicable	No color

Here are the RGB triplets and hexadecimal color codes for the default colors MATLAB uses in many types of plots.

RGB Triplet	Hexadecimal Color Code	Appearance
[0 0.4470 0.7410]	'#0072BD'	
[0.8500 0.3250 0.0980]	'#D95319'	
[0.9290 0.6940 0.1250]	'#EDB120'	
[0.4940 0.1840 0.5560]	'#7E2F8E'	
[0.4660 0.6740 0.1880]	'#77AC30'	
[0.3010 0.7450 0.9330]	'#4DBEEE'	
[0.6350 0.0780 0.1840]	'#A2142F'	

Example: 'blue'

Example: [0 0 1]

Example: '#0000FF'

VisibilityMode — Visibility mode of ground track

'inherit' (default) | 'manual'

Visibility mode of the ground track, specified as either one of these values:

- 'inherit' — Visibility of the graphic matches that of the parent

- 'manual' — Visibility of the graphic is not inherited and is independent of that of the parent

Object Functions

show Show object in satellite scenario viewer

hide

See Also

Objects

satelliteScenario | satelliteScenarioViewer

Functions

access | groundStation | hide | play | satellite | show

Topics

“Satellite Scenario Key Concepts” on page 2-61

Introduced in R2021a

HeadingIndicator Properties

Control heading indicator appearance and behavior

Description

Heading indicators are components that represent a heading indicator. Properties control the appearance and behavior of a heading indicator. Use dot notation to refer to a particular object and property:

```
f = uifigure;  
heading = uiaeroheading(f);  
heading.Value = 100;
```

The heading indicator displays measurements for aircraft heading in degrees.

The heading indicator represents values between 0 and 360 degrees.

Properties

Heading Indicator

Heading — Location of aircraft heading

0 (default) | finite, real, and scalar numeric

Location of the aircraft heading, specified as any finite and scalar numeric, in degrees.

- Changing the value changes the direction of the heading. It displays the exact value.

Example: 60

Dependencies

Specifying this value changes the value of `Value`.

Data Types: `double`

Value — Location of aircraft heading

0 (default) | finite, real, and scalar numeric

Location of the aircraft heading, specified as any finite and scalar numeric, in degrees.

- Changing the value changes the direction of the heading.

Example: 60

Dependencies

Specifying this value changes the value of `Heading`.

Data Types: `double`

Interactivity

Visible — Visibility of heading indicator

'on' (default) | on/off logical value

Visibility of the heading indicator, specified as 'on' or 'off', or as numeric or logical 1 (true) or 0 (false). A value of 'on' is equivalent to true, and 'off' is equivalent to false. Thus, you can use the value of this property as a logical value. The value is stored as an on/off logical value of type `matlab.lang.OnOffSwitchState`. The `Visible` property determines whether the heading indicator is displayed on the screen. If the `Visible` property is set to 'off', then the entire heading indicator is hidden, but you can still specify and access its properties.

ContextMenu — Context menu

empty `GraphicsPlaceholder` array (default) | `ContextMenu` object

Context menu, specified as a `ContextMenu` object created using the `uicontextmenu` function. Use this property to display a context menu when you right-click on a component.

Enable — Operational state of header indicator

'on' (default) | on/off logical value

Operational state of header indicator, specified as 'on' or 'off', or as numeric or logical 1 (true) or 0 (false). A value of 'on' is equivalent to true, and 'off' is equivalent to false. Thus, you can use the value of this property as a logical value. The value is stored as an on/off logical value of type `matlab.lang.OnOffSwitchState`.

- If you set this property to 'on', then the appearance of the header indicator indicates that the header indicator is operational.
- If you set this property to 'off', then the appearance of the header indicator appears dimmed, indicating that the header indicator is not operational.

Position

Position — Location and size of header indicator

[100 100 120 120] (default) | [left bottom width height]

Location and size of the header indicator relative to the parent container, specified as the vector, [left bottom width height]. This table describes each element in the vector.

Element	Description
left	Distance from the inner left edge of the parent container to the outer left edge of an imaginary box surrounding the header indicator
bottom	Distance from the inner bottom edge of the parent container to the outer bottom edge of an imaginary box surrounding the header indicator
width	Distance between the right and left outer edges of the header indicator
height	Distance between the top and bottom outer edges of the header indicator

All measurements are in pixel units.

The `Position` values are relative to the drawable area of the parent container. The drawable area is the area inside the borders of the container and does not include the area occupied by decorations such as a menu bar or title.

Example: `[200 120 120 120]`

InnerPosition — Inner location and size of heading indicator

`[100 100 120 120]` (default) | `[left bottom width height]`

Inner location and size of the heading indicator, specified as `[left bottom width height]`. Position values are relative to the parent container. All measurements are in pixel units. This property value is identical to the `Position` property.

OuterPosition — Outer location and size of heading indicator

`[100 100 120 120]` (default) | `[left bottom width height]`

This property is read-only.

Outer location and size of the heading indicator returned as `[left bottom width height]`. Position values are relative to the parent container. All measurements are in pixel units. This property value is identical to the `Position` property.

Layout — Layout options

empty `LayoutOptions` array (default) | `GridLayoutOptions` object

Layout options, specified as a `GridLayoutOptions` object. This property specifies options for components that are children of grid layout containers. If the component is not a child of a grid layout container (for example, it is a child of a figure or panel), then this property is empty and has no effect. However, if the component is a child of a grid layout container, you can place the component in the desired row and column of the grid by setting the `Row` and `Column` properties on the `GridLayoutOptions` object.

For example, this code places an heading indicator in the third row and second column of its parent grid.

```
g = ui([4 3]);
gauge = uiaeroheading(g);
gauge.Layout.Row = 3;
gauge.Layout.Column = 2;
```

To make the heading indicator span multiple rows or columns, specify the `Row` or `Column` property as a two-element vector. For example, this heading indicator spans columns 2 through 3:

```
gauge.Layout.Column = [2 3];
```

Callbacks

CreateFcn — Creation function

`' '` (default) | function handle | cell array | character vector

Object creation function, specified as one of these values:

- Function handle.
- Cell array in which the first element is a function handle. Subsequent elements in the cell array are the arguments to pass to the callback function.

- Character vector containing a valid MATLAB expression (not recommended). MATLAB evaluates this expression in the base workspace.

For more information about specifying a callback as a function handle, cell array, or character vector, see “Write Callbacks in App Designer”.

This property specifies a callback function to execute when MATLAB creates the object. MATLAB initializes all property values before executing the `CreateFcn` callback. If you do not specify the `CreateFcn` property, then MATLAB executes a default creation function.

Setting the `CreateFcn` property on an existing component has no effect.

If you specify this property as a function handle or cell array, you can access the object that is being created using the first argument of the callback function. Otherwise, use the `gcbo` function to access the object.

DeleteFcn – Deletion function

' ' (default) | function handle | cell array | character vector

Object deletion function, specified as one of these values:

- Function handle.
- Cell array in which the first element is a function handle. Subsequent elements in the cell array are the arguments to pass to the callback function.
- Character vector containing a valid MATLAB expression (not recommended). MATLAB evaluates this expression in the base workspace.

For more information about specifying a callback as a function handle, cell array, or character vector, see “Write Callbacks in App Designer”.

This property specifies a callback function to execute when MATLAB deletes the object. MATLAB executes the `DeleteFcn` callback before destroying the properties of the object. If you do not specify the `DeleteFcn` property, then MATLAB executes a default deletion function.

If you specify this property as a function handle or cell array, you can access the object that is being deleted using the first argument of the callback function. Otherwise, use the `gcbo` function to access the object.

Callback Execution Control

Interruptible – Callback interruption

'on' (default) | on/off logical value

Callback interruption, specified as 'on' or 'off', or as numeric or logical 1 (true) or 0 (false). A value of 'on' is equivalent to `true`, and 'off' is equivalent to `false`. Thus, you can use the value of this property as a logical value. The value is stored as an on/off logical value of type `matlab.lang.OnOffSwitchState`.

This property determines if a running callback can be interrupted. There are two callback states to consider:

- The running callback is the currently executing callback.
- The interrupting callback is a callback that tries to interrupt the running callback.

Whenever MATLAB invokes a callback, that callback attempts to interrupt the running callback (if one exists). The `Interruptible` property of the object owning the running callback determines if interruption is allowed.

- A value of `'on'` allows other callbacks to interrupt the object's callbacks. The interruption occurs at the next point where MATLAB processes the queue, such as when there is a `drawnow`, `figure`, `uifigure`, `getframe`, `waitfor`, or `pause` command.
 - If the running callback contains one of those commands, then MATLAB stops the execution of the callback at that point and executes the interrupting callback. MATLAB resumes executing the running callback when the interrupting callback completes.
 - If the running callback does not contain one of those commands, then MATLAB finishes executing the callback without interruption.
- A value of `'off'` blocks all interruption attempts. The `BusyAction` property of the object owning the interrupting callback determines if the interrupting callback is discarded or put into a queue.

Note Callback interruption and execution behave differently in these situations:

- If the interrupting callback is a `DeleteFcn`, `CloseRequestFcn` or `SizeChangedFcn` callback, then the interruption occurs regardless of the `Interruptible` property value.
- If the running callback is currently executing the `waitfor` function, then the interruption occurs regardless of the `Interruptible` property value.
- Timer objects execute according to schedule regardless of the `Interruptible` property value.

When an interruption occurs, MATLAB does not save the state of properties or the display. For example, the object returned by the `gca` or `gcf` command might change when another callback executes.

BusyAction — Callback queuing

`'queue'` (default) | `'cancel'`

Callback queuing, specified as `'queue'` or `'cancel'`. The `BusyAction` property determines how MATLAB handles the execution of interrupting callbacks. There are two callback states to consider:

- The running callback is the currently executing callback.
- The interrupting callback is a callback that tries to interrupt the running callback.

Whenever MATLAB invokes a callback, that callback attempts to interrupt a running callback. The `Interruptible` property of the object owning the running callback determines if interruption is permitted. If interruption is not permitted, then the `BusyAction` property of the object owning the interrupting callback determines if it is discarded or put in the queue. These are possible values of the `BusyAction` property:

- `'queue'` — Puts the interrupting callback in a queue to be processed after the running callback finishes execution.
- `'cancel'` — Does not execute the interrupting callback.

BeingDeleted — Deletion status

on/off logical value

This property is read-only.

Deletion status, returned as an on/off logical value of type `matlab.lang.OnOffSwitchState`.

MATLAB sets the `BeingDeleted` property to 'on' when the `DeleteFcn` callback begins execution. The `BeingDeleted` property remains set to 'on' until the component object no longer exists.

Check the value of the `BeingDeleted` property to verify that the object is not about to be deleted before querying or modifying it.

Parent/Child

Parent — Parent container

Figure object (default) | Panel object | Tab object | ButtonGroup object | GridLayout object

Parent container, specified as a `Figure` object created using the `uifigure` function, or one of its child containers: `Tab`, `Panel`, `ButtonGroup`, or `GridLayout`. If no container is specified, MATLAB calls the `uifigure` function to create a new `Figure` object that serves as the parent container.

HandleVisibility — Visibility of object handle

'on' (default) | 'callback' | 'off'

Visibility of the object handle, specified as 'on', 'callback', or 'off'.

This property controls the visibility of the object in its parent's list of children. When an object is not visible in its parent's list of children, it is not returned by functions that obtain objects by searching the object hierarchy or querying properties. These functions include `get`, `findobj`, `clf`, and `close`. Objects are valid even if they are not visible. If you can access an object, you can set and get its properties, and pass it to any function that operates on objects.

HandleVisibility Value	Description
'on'	The object is always visible.
'callback'	The object is visible from within callbacks or functions invoked by callbacks, but not from within functions invoked from the command line. This option blocks access to the object at the command-line, but allows callback functions to access it.
'off'	The object is invisible at all times. This option is useful for preventing unintended changes to the UI by another function. Set the <code>HandleVisibility</code> to 'off' to temporarily hide the object during the execution of that function.

Identifiers

Type — Type of graphics object

'uiaeroheading'

This property is read-only.

Type of graphics object, returned as 'uiaeroheading'.

Tag — Object identifier

' ' (default) | character vector | string scalar

Object identifier, specified as a character vector or string scalar. You can specify a unique `Tag` value to serve as an identifier for an object. When you need access to the object elsewhere in your code, you can use the `findobj` function to search for the object based on the `Tag` value.

UserData – User data

[] (default) | array

User data, specified as any MATLAB array. For example, you can specify a scalar, vector, matrix, cell array, character array, table, or structure. Use this property to store arbitrary data on an object.

If you are working in App Designer, create public or private properties in the app to share data instead of using the `UserData` property. For more information, see “Share Data Within App Designer Apps”.

See Also`uiaeroheading`**Topics**

“Create and Configure Flight Instrument Component and an Animation Object” on page 2-49

“Display Flight Trajectory Data Using Flight Instruments and Flight Animation” on page 5-111

Introduced in R2018b

hide

Package: satelliteScenario

Hides satellite scenario entity from viewer

Syntax

```
hide(item)
hide(item,v)
```

Description

hide(item) hides item from all open satellite scenario viewers.

hide(item,v) hides the specified satellite scenario entity on the satellite scenario viewer specified by v.

Input Arguments

item – Item

Satellite object | GroundStation object | ConicalSensor object | GroundTrack object | FieldOfView object | Access object

Satellite, GroundStation, ConicalSensors, GroundTrack, FieldOfView, or Access object. These objects must belong to the same satelliteScenario, object.

v – Satellite scenario viewer

satelliteScenarioViewer object

Satellite scenario viewer, specified as a satelliteScenarioViewer.

See Also

Objects

satellite | satelliteScenarioViewer

Functions

access | groundStation | hideAll | play | satelliteScenario | show | showAll

Topics

“Satellite Scenario Key Concepts” on page 2-61

Introduced in R2021a

hide

Class: Aero.Animation

Package: Aero

Hide animation figure

Syntax

```
hide(h)  
h.hide
```

Description

`hide(h)` and `h.hide` hide (close) the figure for the animation object `h`. Use `show` to redisplay the animation object figure.

Input Arguments

`h` Animation object.

Examples

Hide the animation object figure that the `show` method displays.

```
h=Aero.Animation;  
h.show;  
h.hide;
```


hideAll

Package: satelliteScenario

Hide all graphics in satellite scenario viewer

Syntax

```
hideAll(viewer)
```

Description

hideAll(viewer) hides all graphics in the specified satellite scenario viewer.

Input Arguments

viewer — Satellite scenario viewer

satelliteScenarioViewer object

Satellite scenario viewer, specified as a satelliteScenarioViewer object. viewer must be specified as a scalar satelliteScenarioViewer object.⁸

See Also

Objects

satelliteScenario | satelliteScenarioViewer

Functions

access | camheading | camheight | campitch | campos | camroll | camtarget | conicalSensor | groundStation | hide | play | show | showAll

Topics

“Satellite Scenario Key Concepts” on page 2-61

Introduced in R2021a

8. Alignment of boundaries and region labels are a presentation of the feature provided by the data vendors and do not imply endorsement by MathWorks.

igrfmagm

Calculate Earth magnetic field and secular variation using International Geomagnetic Reference Field

Syntax

```
[XYZ,H,D,I,F,DXDYDZ,DH,DD,DI,DF] = igrfmagm(height,latitude,longitude,decimalYear)
```

```
[XYZ,H,D,I,F,DXDYDZ,DH,DD,DI,DF] = igrfmagm(height,latitude,longitude,decimalYear,generation)
```

Description

[XYZ,H,D,I,F,DXDYDZ,DH,DD,DI,DF] = igrfmagm(height,latitude,longitude,decimalYear) calculates the Earth magnetic field and the secular variation at a specific location and time using the International Geomagnetic Reference Field generation 13 (IGRF-13).

[XYZ,H,D,I,F,DXDYDZ,DH,DD,DI,DF] = igrfmagm(height,latitude,longitude,decimalYear,generation) optionally uses different generations of the International Geomagnetic Reference Field (IGRF-13, IGRF-12, and IGRF-11).

Examples

Calculate the Magnetic Model

Calculate the magnetic model 1000 meters over Natick, Massachusetts on July 4, 2015 using IGRF-13.

```
[XYZ,H,D,I,F] ...
= igrfmagm(1000,42.283,-71.35,decyear(2015,7,4),13)
```

```
XYZ =
    1.0e+04 *
    1.9471    -0.5086    4.8177
```

```
H =
    2.0124e+04
```

```
D =
   -14.6381
```

```
I =
    67.3295
```

```
F =
    5.2212e+04
```

Calculate the Magnetic Model with Matrix inputs

Calculate the magnetic model at 0 and 10000 km over Lawrence, Kansas on May 15, 2018 using IGRF-13.

```
h = [0,10000000]
lat = [38.957114,38.957114]
lon = [-95.253997,-95.253997]
dyear = [decyear(2018,5,14), decyear(2018,5,14)]
[XYZ,H,D,I,F] = igrfmagm(h,lat,lon,dyear,13)
```

```
h =
      0      10000000

lat =
    38.9571    38.9571

lon =
   -95.2540   -95.2540

dyear =
    1.0e+03 *
    2.0184    2.0184

XYZ =
    1.0e+04 *
    2.0655    0.0783    4.7990
    0.1192    0.0046    0.2571

H =
    1.0e+04 *
    2.0670
    0.1193

D =
    2.1714
    2.1968

I =
    66.6981
    65.1016

F =
    1.0e+04 *
    5.2252
    0.2834
```

Input Arguments

height — Distance

matrix | scalar | vector

Distance from the surface of the Earth, specified as a matrix, scalar, or vector, in meters.

Data Types: double

Latitude — Geodetic latitude

scalar | vector | matrix

Geodetic latitude, specified as a matrix, scalar, or vector, in degrees. North latitude is positive and south latitude is negative.

This function accepts latitude values greater than 90 and less than -90.

Data Types: double

Longitude — Geodetic longitude

matrix | scalar | vector

Geodetic longitude specified as a matrix, scalar, or vector, in degrees. East longitude is positive and west longitude is negative. This function accepts ranges greater than 180 and less than -180.

Data Types: double

decimalYear — Year

matrix | scalar | vector

Year, in decimal format, specified as a matrix. This value can have any fraction of the year that has already passed.

Data Types: double

generation — Generation version of International Geomagnetic Reference Field

13 (default) | 12 | 11 | scalar numeric

Generation version of the International Geomagnetic Reference Field, specified as 13, 12, or 11.

Data Types: single | double | int8 | int16 | int32 | int64 | uint8 | uint16 | uint32 | uint64 | char | string

Output Arguments**XYZ — Magnetic field vector**

vector | matrix

Magnetic field vector, in nanotesla (nT), returned as a vector or matrix the same size as the input matrix with an additional dimension, the last dimension. The last dimension of the matrix is of size 3, specifying the X, Y, and Z components of the magnetic field. Z is the vertical component (+ve down). The components of this vector are in the north-east-down (NED) reference frame.

Data Types: double

H — Horizontal intensity

scalar | vector | matrix

Horizontal intensity, returned as a scalar, vector, or matrix, in nanotesla (nT), the same size as the input matrix.

Data Types: double

D — Declination

scalar | vector | matrix

Declination, returned as a scalar, in degrees (+ve east), the same size as the input matrix.

Data Types: double

I – Inclination

scalar | vector | matrix

Inclination, returned as a scalar, in degrees (+ve down), the same size as the input matrix.

Data Types: double

F – Total intensity

scalar | vector | matrix

Total intensity, returned as a scalar, in nanotesla (nT), the same size as the input matrix.

Data Types: double

DXDYDZ – Secular variation in magnetic field vector

vector | matrix

Secular variation in magnetic field vector, returned as a vector or matrix, in nT/year, the same size as the input matrix with an additional dimension, the last dimension. The last dimension of the matrix is of size 3, specifying the X, Y, and Z components of the magnetic field. Z is the vertical component (+ve down).

Data Types: double

DH – Secular variation in horizontal intensity

scalar | vector | matrix

Secular variation in horizontal intensity, in nT/year, returned as a scalar, the same size as the input matrix.

Data Types: double

DD – Secular variation in declination

scalar | vector | matrix

Secular variation in declination, in minutes/year (+ve east), returned as a scalar, the same size as the input matrix.

Data Types: double

DI – Secular variation in inclination

scalar | vector | matrix

Secular variation in inclination, in minutes/year (+ve down), returned as a scalar, the same size as the input matrix.

Data Types: double

DF – Secular variation in total intensity

scalar | vector | matrix

Secular variation in total intensity, in nT/year, returned as a scalar, the same size as the input matrix.

Data Types: double

Limitation

- This function is valid for these year ranges:
 - IGRF-13 model — 1900 and 2025
 - IGRF-12 model — 1900 and 2020
 - IGRF-11 model — 1900 and 2015
- This function is valid between the heights of -1000 m and 5.6 Earth radii (35,717,567.2 m).
- The height, latitude, longitude, and decimalYear arguments must all be the same size (matrix, scalar, and so forth).

This function has the limitations of the International Geomagnetic Reference Field (IGRF). For more information, see the IGRF website, <https://www.ngdc.noaa.gov/IAGA/vmod/igrfhw.html>.

References

- [1] Blakely, R. J. *Potential Theory in Gravity & Magnetic Applications*. Cambridge, UK: Cambridge University Press, 1996.
- [2] Lowes, F. J. "The International Geomagnetic Reference Field: A 'Health' Warning." January, 2010. <https://www.ngdc.noaa.gov/IAGA/vmod/igrfhw.html>.

See Also

decyear | wrldmagm

External Websites

<https://www.ngdc.noaa.gov/IAGA/vmod/igrfhw.html>

Introduced in R2015b

ijk2keplerian

Keplerian orbit elements using position and velocity vectors

Syntax

```
[a,ecc,incl,RAAN,argp,nu,truelon,arglat,lonper] = ijk2keplerian(r_ijk, v_ijk)
```

Description

[a,ecc,incl,RAAN,argp,nu,truelon,arglat,lonper] = ijk2keplerian(r_ijk, v_ijk) calculates Keplerian orbit elements for given position and velocity vectors in the geocentric equatorial coordinate system.

Examples

Convert IJK Position and Velocity

Convert the geocentric equatorial coordinate system (IJK) position and velocity to Keplerian orbital elements.

```
r_ijk = [-2981784 5207055 3161595];
v_ijk = [-3384 -4887 4843];
[a, ecc, incl, RAAN, argp, nu, truelon, arglat, lonper] = ...
    ijk2keplerian(r_ijk, v_ijk)
```

```
a =
    6.7845e+06
```

```
ecc =
    9.1950e-04
```

```
incl =
    51.7528
```

```
RAAN =
    95.2570
```

```
argp =
    106.4005
```

```
nu =
    290.0096
```

```
truelon =
    NaN
```

```
arglat =
    NaN
```

```
lonper =  
    NaN
```

Input Arguments

r_ijk — Position component

0 (default) | 3-by-1 array

Geocentric equatorial position components, specified as a 3-by-1 array, in meters.

Data Types: `double`

v_ijk — Velocity component

0 (default) | 3-by-1 array

Geocentric equatorial velocity components, specified as a 3-by-1 array, in m/s.

Data Types: `double`

Output Arguments

a — Semi-major axis

scalar

Semimajor axis (half of the longest diameter) of the orbit, returned as a scalar, in meters.

Data Types: `double`

ecc — Orbit eccentricity

scalar value greater than or equal to 0

Orbit eccentricity (deviation of orbital curve from circular), returned as a scalar.

Data Types: `double`

incl — Inclination

scalar value from 0 to 180

Inclination (tilt angle) of the orbit, in degrees.

Data Types: `double`

RAAN — Right ascension of ascending node

scalar value from 0 to 360

Angle in the equatorial plane from the x-axis to the location of the ascending node (point at which the satellite crosses the equator from south to north), in degrees.

Data Types: `double`

argp — Angle between CubeSat ascending node and periapsis

scalar value from 0 to 360

Angle between the CubeSat ascending node and periapsis (closest point of orbit to Earth), in degrees.

Data Types: `double`

nu — Angle between periapsis and current position of CubeSat

scalar value from 0 to 360

Angle between periapsis and current position of CubeSat, in degrees.

Data Types: double

trueLon — Angle between x-axis and CubeSat position vector

scalar value from 0 to 360

Angle between the x-axis and CubeSat position vector, in degrees.

Data Types: double

argLat — Angle between ascending node and CubeSat position vector

scalar value from 0 to 360

Angle between the ascending node and the CubeSat position vector, in degrees.

Data Types: double

lonper — Angle between x-axis and eccentricity vector

scalar value from 0 to 360

Angle between the x-axis and the eccentricity vector, in degrees.

Data Types: double

References

[1] Vallado, D. A. *Fundamentals of Astrodynamics and Applications*. alg. 5. McGraw-Hill, 1997.

See Also

CubeSat Vehicle | aeroReadIERSData | dcmeci2ecef | deltaCIP | deltaUT1 | ecef2eci | eci2ecef | keplerian2ijk | polarMotion | siderealTime

Introduced in R2019a

initialize

Class: Aero.Animation

Package: Aero

Create animation object figure and axes and build patches for bodies

Syntax

```
initialize(h)  
h.initialize
```

Description

`initialize(h)` and `h.initialize` create a figure and axes for the animation object `h`, and builds patches for the bodies associated with the animation object. If there is an existing figure, this function

- 1 Clears out the old figure and its patches.
- 2 Creates a new figure and axes with default values.
- 3 Repopulates the axes with new patches using the surface to patch data from each body.

Input Arguments

`h` Animation object.

Examples

Initialize the animation object, `h`.

```
h = Aero.Animation;  
h.initialize();
```

initialize (Aero.FlightGearAnimation)

Set up FlightGear animation object

Syntax

```
initialize(h)  
h.initialize
```

Description

`initialize(h)` and `h.initialize` set up the FlightGear version, IP address, and socket for the FlightGear animation object `h`.

Examples

Initialize the animation object, `h`.

```
h = Aero.FlightGearAnimation;  
h.initialize();
```

See Also

[GenerateRunScript](#) | [delete](#) | [play](#) | [update](#)

Introduced in R2007a

initialize (Aero.VirtualRealityAnimation)

Create and populate virtual reality animation object

Syntax

```
initialize(h)  
h.initialize
```

Description

`initialize(h)` and `h.initialize` create a virtual reality animation world and populate the virtual reality animation object `h`. If a previously initialized virtual reality animation object exists, and that object has user-specified data, this function saves the previous object to be reset after the initialization.

Examples

Initialize the virtual reality animation object, `h`.

```
h = Aero.VirtualRealityAnimation;  
h.VRWorldFilename = [matlabroot, '/toolbox/aero/astdemos/asttkoff.wrl'];  
copyfile(h.VRWorldFilename, [tempdir, 'asttkoff.wrl'], 'f');  
h.VRWorldFilename = [tempdir, 'asttkoff.wrl'];  
h.initialize();
```

See Also

`delete` | `play`

Introduced in R2007b

initIfNeeded

Class: Aero.Animation

Package: Aero

Initialize animation graphics if needed

Syntax

```
initIfNeeded(h)  
h.initIfNeeded
```

Description

`initIfNeeded(h)` and `h.initIfNeeded` initialize animation object graphics if necessary.

Input Arguments

`h` Animation object.

Examples

Initialize the animation object graphics of `h` as needed.

```
h=Aero.Animation;  
h.initIfNeeded;
```

juliandate

Julian date calculator

Syntax

```
jd = juliandate(dateVector)
jd = juliandate(dateCharacterVector, format)

jd = juliandate(year, month, day)
dy = juliandate([year, month, day])
jd = juliandate(year, month, day, hour, minute, second)
dy = juliandate([year, month, day, hour, minute, second])
```

Description

`jd = juliandate(dateVector)` converts one or more date vectors, `dateVector`, to Julian date, `jd`.

`jd = juliandate(dateCharacterVector, format)` converts one or more date character vectors, `dateCharacterVector`, to Julian date, `jd`, using format `format`.

`jd = juliandate(year, month, day)` and `dy = juliandate([year, month, day])` return the Julian date for corresponding elements of the `year`, `month`, `day` arrays.

`jd = juliandate(year, month, day, hour, minute, second)` and `dy = juliandate([year, month, day, hour, minute, second])` return the Julian date for corresponding elements of the `year`, `month`, `day`, `hour`, `minute`, `second` arrays. Specify the six arguments as one-dimensional arrays of the same length or scalar values.

Examples

Calculate Julian Date Using Date Character Version and dd-mm-yyyy Format

Calculate Julian date for May 24, 2005 using date character version and dd-mm-yyyy format:

```
jd = juliandate('24-May-2005', 'dd-mmm-yyyy')

jd =
  2.4535e+06
```

Calculate Julian Date Using Year, Month, and Day Inputs

Calculate Julian date for December 19, 2006 from year, month, and day inputs:

```
jd = juliandate(2006, 12, 19)
```

```
jd =
    2.4541e+06
```

Calculate Julian Date from Year, Month, Day, Hour, Minute, and Second Inputs

Calculate Julian date for October 10, 2004, at 12:21:00 p.m. from year, month, day, hour, month, and second inputs:

```
jd = juliandate(2004,10,10,12,21,0)
```

```
jd =
    2.4533e+006
```

Input Arguments

dateVector — Full or partial date vector

m-by-6 matrix | *m*-by-3 matrix | positive double-precision number

Full or partial date vector, specified as an *m*-by-6 or *m*-by-3 matrix containing *m* full or partial date vectors, respectively:

- Full date vector — Contains six elements specifying the year, month, day, hour, minute, and second
- Partial date vector — Contains three elements specifying the year, month, and day

Data Types: double

dateCharacterVector — Date character vector

character array | one-dimensional cell array of character vectors

Date character vector, specified as a character array, where each row corresponds to one date, or a one-dimensional cell array of character vectors.

Data Types: char | string

format — Date format

-1 (default) | character vector | string scalar | integer

Date format, specified as a character vector, string scalar, or integer. All dates in `dateCharacterVector` must have the same format and use the same date format symbols as the `datenum` function.

`juliandate` does not accept formats containing the letter *Q*.

If the format does not contain enough information to compute a date number, then:

- Hours, minutes, and seconds default to 0.
- Days default to 1.
- Months default to January.
- Years default to the current year.

Data Types: char | string

year — Year

current year (default) | scalar | one-dimensional array

Year, specified as a scalar or one-dimensional array.

Dates with two character years are interpreted to be within 100 years of the current year.

Dependencies

Depending on the syntax, specify **year**, **month**, and **day** or **year**, **month**, **day**, **hour**, **minute**, and **second** as one-dimensional arrays of the same length or scalar values.

Data Types: char | string

month — Month

1 (default) | 2 | 3 | 4 | 5 | 6 | 7 | 8 | 9 | 10 | 11 | 12 | one-dimensional array

Month, specified as a scalar or one-dimensional array from 1 to 12.

Dependencies

Depending on the syntax, specify **year**, **month**, and **day** or **year**, **month**, **day**, **hour**, **minute**, and **second** as one-dimensional arrays of the same length or scalar values.

Data Types: double

day — Day

1 (default) | 2 | 3 | 4 | 5 | 6 | 7 | 8 | 9 | 10 | 11 | 12 | 13 | 14 | 15 | 16 | 17 | 18 | 19 | 20 | 21 | 22 | 23 | 24 | 25 | 26 | 27 | 28 | 29 | 30 | 31 | one-dimensional array

Day, specified as a scalar or one-dimensional array from 1 to 31.

Dependencies

Depending on the syntax, specify **year**, **month**, and **day** or **year**, **month**, **day**, **hour**, **minute**, and **second** as one-dimensional arrays of the same length or scalar values.

Data Types: double

hour — Date format

0 (default) | double, whole number, 0 to 24

Hour, specified as a scalar from 0 to 24.

Dependencies

Depending on the syntax, specify **year**, **month**, and **day** or **year**, **month**, **day**, **hour**, **minute**, and **second** as one-dimensional arrays of the same length or scalar values.

Data Types: double

minute — Minute

0 (default) | double, whole number, 0 to 60

Minute, specified as a double, whole number from 0 to 60.

Dependencies

Depending on the syntax, specify **year**, **month**, and **day** or **year**, **month**, **day**, **hour**, **minute**, and **second** as one-dimensional arrays of the same length or scalar values.

Data Types: double

second — Second

0 (default) | double, whole number, 0 to 60

Second, specified as a double, whole number from 0 to 60.

Dependencies

Depending on the syntax, specify year, month, and day or year, month, day, hour, minute, and second as one-dimensional arrays of the same length or scalar values.

Data Types: double

Output Arguments

jd — Julian date

m-by-6 column vector | *m*-by-3 column vector

Julian date, returned as a column vector of *m* Julian dates, which are the number of days and fractions since noon Universal Time on January 1, 4713 BCE.

- *m*-by-6 column vector — Contains six elements specifying the year, month, day, hour, minute, and second
- *m*-by-3 column vector — Contains three elements specifying the year, month, and day

Dependencies

The output format depends on the input format:

Input Syntax	dy Format
<code>jd = juliandate(dateVector)</code>	<i>m</i> -by-6 column vector or <i>m</i> -by-3 column vector of <i>m</i> Julian dates.
<code>jd = juliandate(dateCharacterVector, format)</code>	Column vector of <i>m</i> Julian dates, where <i>m</i> is the number of character vectors in <code>dateCharacterVector</code> .

Limitations

The calculation of Julian date does not take into account leap seconds.

See Also

`datenum` | `datestr` | `decyear` | `leapyear` | `mjuliandate`

Introduced in R2006b

keplerian2ijk

Position and velocity vectors in geocentric equatorial coordinate system using Keplerian orbit elements

Syntax

```
[r_ijk,v_ijk] = keplerian2ijk(a,ecc,incl,RAAN,argp,nu)
[r_ijk,v_ijk] = keplerian2ijk( ___,Name,Value)
```

Description

`[r_ijk,v_ijk] = keplerian2ijk(a,ecc,incl,RAAN,argp,nu)` calculates the position and velocity vectors in the geocentric equatorial coordinate system (IJK) for given Keplerian orbit elements of noncircular, inclined orbits.

`[r_ijk,v_ijk] = keplerian2ijk(___,Name,Value)` specifies orbit element properties using one or more name-value pair arguments. For example, 'truelon', '17' specifies the angle between the x-axis and CubeSat position vector. Specify name-value pair arguments after all other input arguments.

Examples

Convert Keplerian Orbital Elements

Convert Keplerian orbital elements to geocentric equatorial coordinate system (IJK) position and velocity.

```
a = 6786230;
ecc = .01;
incl = 52;
RAAN = 95;
argp = 93;
nu = 300;
[r_ijk, v_ijk] = keplerian2ijk(a, ecc, incl, RAAN, argp, nu)
```

```
r_ijk =
    1.0e+06 *
    -2.7489
     5.4437
     2.8977
```

```
v_ijk =
    1.0e+03 *
    -3.5694
    -4.5794
     5.0621
```

Convert Keplerian Orbital Elements for Equatorial Orbit

Convert Keplerian orbital elements to geocentric equatorial coordinate system (IJK) position and velocity for equatorial orbit.

```
a = 6786230;
ecc = .1;
incl = 0;
RAAN = 95;
argp = 93;
nu = 300;
lonper = 45;
[r_ijk, v_ijk] = keplerian2ijk(a, ecc, incl, RAAN, argp, nu, 'lonper', lonper)
```

```
r_ijk =
    1.0e+06 *
    6.1804
   -1.6560
         0
```

```
v_ijk =
    1.0e+03 *
    1.4489
    7.9848
         0
```

Input Arguments

a — Semi-major axis

scalar

Semimajor axis (half of the longest diameter) of the orbit, specified as a scalar, in meters.

Data Types: double

ecc — Orbit eccentricity

0 (default) | scalar value greater than or equal to 0

Orbit eccentricity (deviation of orbital curve from circular), specified as a scalar.

Data Types: double

incl — Inclination

0 (default) | scalar value from 0 to 180

Inclination (tilt angle) of the orbit, in degrees.

Data Types: double

RAAN — Right ascension of ascending node

0 (default) | scalar value from 0 to 360

Angle in the equatorial plane from the x-axis to the location of the ascending node, point at which the satellite crosses the equator from south to north, in degrees. The function does not use this value for equatorial orbits.

Data Types: double

argp — Angle between CubeSat ascending node and periapsis θ (default) | scalar value from 0 to 360

Angle between the CubeSat ascending node and the periapsis (closest point of orbit to Earth), in degrees. The function does not use this value for circular and equatorial orbits.

Data Types: double

nu — Angle between periapsis and current position of CubeSat θ (default) | scalar value from 0 to 360

Angle between the periapsis and the current position of CubeSat, in degrees. The function does not use this value for circular orbits.

Data Types: double

Name-Value Pair Arguments

Specify optional comma-separated pairs of `Name`, `Value` arguments. `Name` is the argument name and `Value` is the corresponding value. `Name` must appear inside quotes. You can specify several name and value pair arguments in any order as `Name1, Value1, . . . , NameN, ValueN`.

Example: 45

trueLon — Angle between x-axis and CubeSat position vector θ (default) | scalar value from 0 to 360

Angle between the x-axis and the CubeSat position vector, in degrees. The function uses this value only for circular equatorial orbits (where eccentricity and inclination are zero).

Data Types: double

argLat — Angle between ascending node and CubeSat position vector θ (default) | scalar value from 0 to 360

Angle between the ascending node and the CubeSat position vector, in degrees. The function uses this value only for circular inclined orbits (where eccentricity is zero and inclination is nonzero).

Data Types: double

lonper — Angle between x-axis and eccentricity vector θ | scalar value from 0 to 360

Angle between the x-axis and the eccentricity vector, in degrees. The function uses this value only for noncircular equatorial orbits (where eccentricity is nonzero and inclination is zero).

Data Types: double

Output Arguments**r_ijk — Position component**

3-by-1 array

Geocentric equatorial position components, returned as a 3-by-1 array, in meters.

v_ijk — Velocity component

3-by-1 array

Geocentric equatorial velocity components, returned as a 3-by-1 array, in m/s.

References

[1] Vallado, D. A. *Fundamentals of Astrodynamics and Applications*. alg. 5. McGraw-Hill, 1997.

See Also

CubeSat Vehicle | aeroReadIERSData | dcmeci2ecef | deltaCIP | deltaUT1 | ecef2eci | eci2ecef | ijk2keplerian | keplerian2ijk | polarMotion | siderealTime

Introduced in R2019a

leapyear

Determine leap year

Syntax

```
ly = leapyear(year)
```

Description

`ly = leapyear(year)` determines whether one or more years are leap years or not. The output, `ly`, is a logical array. `year` must be numeric. Non-integer values are floored to the nearest integer value.

Examples

Determine whether 2005 is a leap year:

```
ly = leapyear(2005)
```

```
ly =
```

```
0
```

Determine whether 2000, 2005, and 2020 are leap years:

```
ly = leapyear([2000 2005 2020])
```

```
ly =
```

```
1    0    1
```

Assumptions and Limitations

The determination of leap years is done by Gregorian calendar rules.

See Also

`decyear` | `juliandate` | `mjuliandate`

Introduced in R2006b

linearize

Class: Aero.FixedWing

Package: Aero

Return linear state-space model

Syntax

```
linsys = linearize(aircraft, state)
linsys = linearize( ____, Name, Value)
```

Description

`linsys = linearize(aircraft, state)` returns a linear state-space representation of a fixed-wing aircraft linearized around a point given by `state`.

`linsys = linearize(____, Name, Value)` returns the linear system using additional options specified by one or more `Name, Value` pair arguments.

Input Arguments

aircraft — Aero.FixedWing object

scalar

Aero.FixedWing object, specified as a scalar.

state — Aero.FixedWing.State object

scalar

Aero.FixedWing.State object, specified as a scalar.

Name-Value Pair Arguments

Specify optional comma-separated pairs of `Name, Value` arguments. `Name` is the argument name and `Value` is the corresponding value. `Name` must appear inside quotes. You can specify several name and value pair arguments in any order as `Name1, Value1, ..., NameN, ValueN`.

Example: 'RelativePerturbation', '1e-5'

RelativePerturbation — Relative perturbation

1e-5 (default) | scalar numeric

Relative perturbation of the system, specified as a scalar numeric. This perturbation takes the form of:

Perturbation Type	Definition
System State perturbation	<code>statePert = RelativePerturbation + 1e-3*RelativePerturbation* baseValue </code>

Perturbation Type	Definition
System input perturbation	$\text{ctrlPert} = \text{RelativePerturbation} + 1e-3 * \text{RelativePerturbation} * \text{baseValue} $

To calculate the Jacobian of the system, `linearize` uses the result of these equations in conjunction with the `DifferentialMethod` property.

Example: `'RelativePerturbation', 1e-5`

Data Types: `double`

DifferentialMethod – Direction while perturbing model

`'Forward'` (default) | `'Backward'` | `'Ceentral'`

Direction while perturbing model, specified as:

Direction	Description
<code>'Forward'</code>	Forward difference method that adds <code>statePert</code> and <code>ctrlPert</code> to the base states and inputs, respectively.
<code>'Backward'</code>	Backward difference method that adds <code>statePert</code> and <code>ctrlPert</code> to the base states and inputs, respectively.
<code>'Central'</code>	Central difference method that adds and subtracts <code>statePert</code> and <code>ctrlPert</code> to and from the base states and inputs, respectively.

Example: `'DifferentialMethod', 'Backward'`

Data Types: `char` | `string`

Output Arguments

linSys – Linear state-space model

scalar

Linear state-space model, returned as a scalar. The inputs and outputs of the state-space model depend on the degrees of freedom of the fixed-wing model and the number of control states on the model.

Examples

Calculate Linear State-Space Model

Calculate the linear state-space model of a Cessna 182 during cruise.

```
[C182, CruiseState] = astC182();
linSys = linearize(C182, CruiseState)
```

linSys =

```
A =
```

	XN	XE	XD	U	V	W
--	----	----	----	---	---	---

XN	0	0	0	1	0	0
XE	0	0	0	0	1	0
XD	0	0	0	0	0	1
U	0	0	0	-0.02574	-6.661e-10	0.08865
V	0	0	0	0	-0.1873	0
W	0	0	0	-0.2926	-7.183e-09	-2.115
P	0	0	0	0	-0.1375	0
Q	0	0	0	0.01265	3.331e-10	-0.07866
R	0	0	0	0	0.04268	0
RollAngle	0	0	0	0	0	0
PitchAngle	0	0	0	0	0	0
YawAngle	0	0	0	0	0	0

	P	Q	R	RollAngle	PitchAngle	YawAngle
XN	0	0	0	0	-0.0011	-0.0011
XE	0	0	0	0	0	220.1
XD	0	0	0	0	-220.1	0
U	0	0	0	0	-32.2	0
V	-7.867	0	-197.7	32.2	0	0
W	0	-189	0	-0.000161	-0.000161	0
P	-158.7	0	26.16	0	0	0
Q	0	-388	0	0	0	0
R	-4.37	0	-14.87	0	0	0
RollAngle	1	0	0	0	0	0
PitchAngle	0	1	0	0	0	0
YawAngle	0	0	1	0	0	0

B =

	Aileron	Elevator	Rudder	Propeller
XN	0	0	0	0
XE	0	0	0	0
XD	0	0	0	0
U	0	0	0	2215
V	0	19.62	0	0
W	0	0	-45.11	0
P	75.07	4.819	0	0
Q	0	0	-42.84	0
R	-7.963	-12.78	0	0
RollAngle	0	0	0	0
PitchAngle	0	0	0	0
YawAngle	0	0	0	0

C =

	XN	XE	XD	U	V	W
XN	1	0	0	0	0	0
XE	0	1	0	0	0	0
XD	0	0	1	0	0	0
U	0	0	0	1	0	0
V	0	0	0	0	1	0
W	0	0	0	0	0	1
P	0	0	0	0	0	0
Q	0	0	0	0	0	0
R	0	0	0	0	0	0
RollAngle	0	0	0	0	0	0
PitchAngle	0	0	0	0	0	0
YawAngle	0	0	0	0	0	0

	P	Q	R	RollAngle	PitchAngle	YawAngle
XN	0	0	0	0	0	0
XE	0	0	0	0	0	0
XD	0	0	0	0	0	0
U	0	0	0	0	0	0
V	0	0	0	0	0	0
W	0	0	0	0	0	0
P	1	0	0	0	0	0
Q	0	1	0	0	0	0
R	0	0	1	0	0	0
RollAngle	0	0	0	1	0	0
PitchAngle	0	0	0	0	1	0
YawAngle	0	0	0	0	0	1

D =

	Aileron	Elevator	Rudder	Propeller
XN	0	0	0	0
XE	0	0	0	0
XD	0	0	0	0
U	0	0	0	0
V	0	0	0	0
W	0	0	0	0
P	0	0	0	0
Q	0	0	0	0

R	0	0	0	0
RollAngle	0	0	0	0
PitchAngle	0	0	0	0
YawAngle	0	0	0	0

Continuous-time state-space model.

See Also

[Aero.FixedWing](#) | [forcesAndMoments](#) | [nonlinearDynamics](#) | [staticStability](#)

Introduced in R2021a

lla2ecef

Convert geodetic coordinates to Earth-centered Earth-fixed (ECEF) coordinates

Syntax

```
ecef = lla2ecef(lla)
ecef = lla2ecef(lla,model)
ecef = lla2ecef(lla,f,Re)
```

Description

`ecef = lla2ecef(lla)` converts an m -by-3 array of geodetic coordinates (latitude, longitude and altitude), `lla`, to an m -by-3 array of ECEF coordinates, `ecef`.

`ecef = lla2ecef(lla,model)` converts the coordinates for a specific ellipsoid planet.

`ecef = lla2ecef(lla,f,Re)` converts the coordinates for a custom ellipsoid planet defined by flattening, `f`, and the equatorial radius, `Re`, in meters.

Examples

Determine ECEF Coordinates at Latitude, Longitude, and Altitude

Determine ECEF coordinates at a latitude, longitude, and altitude:

```
p = lla2ecef([0 45 1000])

p =
    1.0e+06 *
    4.5107    4.5107         0
```

Determine ECEF Coordinates at Multiple Latitudes, Longitudes, and Altitudes with WGS84 Ellipsoid Model

Determine ECEF coordinates at multiple latitudes, longitudes, and altitudes using the WGS84 ellipsoid model:

```
p = lla2ecef([0 45 1000; 45 90 2000], 'WGS84')

p =
    1.0e+06 *
    4.5107    4.5107         0
         0    4.5190    4.4888
```

Determine ECEF Coordinates at Multiple Latitudes, Longitudes, and Altitudes with Custom Ellipsoid Model

Determine ECEF coordinates at multiple latitudes, longitudes, and altitudes using the custom ellipsoid model:

```
f = 1/196.877360;
Re = 3397000;
p = \la2ecef([0 45 1000; 45 90 2000], f, Re)
```

```
p =
    1.0e+06 *
     2.4027     2.4027         0
         0     2.4096     2.3852
```

Input Arguments

lla — Geodetic coordinates

m-by-3 array

Geodetic coordinates (latitude, longitude and altitude), specified as an *m*-by-3 array in [degrees degrees meters]. Latitude and longitude values can be any value. However, latitude values of +90 and -90 may return unexpected values because of singularity at the poles. Altitude is above the planetary ellipsoid.

Data Types: double

model — Ellipsoid planet model

'WGS84' (default)

Ellipsoid planet model, specified as 'WGS84'.

Data Types: char | string

f — Flattening

scalar

Flattening at each pole, specified as a scalar.

Data Types: double

Re — Planetary equatorial radius

scalar

Equatorial radius, specified as a scalar, in meters.

Data Types: double

Output Arguments

ecef — ECEF coordinates

m-by-3 array | vector

ECEF coordinates, returned as an *m*-by-3 array of ECEF coordinates.

See Also

[ecef2lla](#) | [geoc2geod](#) | [geod2geoc](#)

Introduced in R2006b

lla2eci

Convert geodetic latitude, longitude, altitude (LLA) coordinates to Earth-centered inertial (ECI) coordinates

Syntax

```
position = lla2eci(lla,utc)
```

```
position = lla2eci(lla,utc,reduction)
```

```
position = lla2eci(lla,utc,reduction,deltaAT)
```

```
position = lla2eci(lla,utc,reduction,deltaAT,deltaUT1)
```

```
position = lla2eci(lla,utc,reduction,deltaAT,deltaUT1,polarmotion)
```

```
position = lla2eci(lla,utc,reduction,deltaAT,deltaUT1,polarmotion,Name,Value)
```

Description

`position = lla2eci(lla,utc)` converts geodetic latitude, longitude, altitude (LLA) coordinates to Earth-centered inertial (ECI) position coordinates as an *M*-by-3 array. The conversion is based on the Universal Coordinated Time (UTC) you specify.

`position = lla2eci(lla,utc,reduction)` converts geodetic latitude, longitude, altitude (LLA) coordinates to Earth-centered inertial (ECI) position coordinates as an *M*-by-3 array. The conversion is based on the specified reduction method and the Universal Coordinated Time (UTC) you specify.

`position = lla2eci(lla,utc,reduction,deltaAT)` uses the difference between International Atomic Time and UTC that you specify as `deltaAT` to calculate the ECI coordinates.

`position = lla2eci(lla,utc,reduction,deltaAT,deltaUT1)` uses the difference between UTC and Universal Time (UT1), which you specify as `deltaUT1`, in the calculation.

`position = lla2eci(lla,utc,reduction,deltaAT,deltaUT1,polarmotion)` uses the polar displacement, `polarmotion`, in the calculation.

`position = lla2eci(lla,utc,reduction,deltaAT,deltaUT1,polarmotion,Name,Value)` uses additional options specified by one or more `Name,Value` pair arguments.

Examples

Convert Position to ECI Coordinates Using UTC

Convert the position to ECI coordinates from LLA coordinates 6 degrees north, 75 degrees west, and 1000 meters altitude at 01/17/2010 10:20:36 UTC.

```
position = lla2eci([6 -75 1000],[2010 1 17 10 20 36])
```

```
position=
```

```
1.0e+06 *
```

```
-6.0744 -1.8289 0.6685
```

Convert Position to ECI coordinates Using UTC and Reduction Method IAU-76/FK5

Convert the position to ECI coordinates from LLA coordinates 55 deg south, 75 deg west, and 500 meters altitude at 01/12/2000 4:52:12.4 UTC. Specify all arguments, including optional ones such as polar motion.

```
position = lla2eci([-55 -75 500],[2000 1 12 4 52 12.4],...
'IAU-76/FK5',32,0.234,[-0.0682e-5 0.1616e-5],...
'dNutation',[-0.2530e-6 -0.0188e-6],...
'flattening',1/290,'RE',60000)
```

```
position=
```

```
1.0e+04 *
-1.1358 3.2875 -4.9333
```

Input Arguments

lla — Latitude, longitude, altitude (LLA) coordinates

M-by-3 array

Latitude, longitude, altitude (LLA) coordinates as *M*-by-3 array of geodetic coordinates, in degrees, degrees, and meters, respectively. Latitude and longitude values can be any value. However, latitude values of +90 and -90 may return unexpected values because of singularity at the poles.

utc — Universal Coordinated Time

1-by-6 array | *M*-by-6 matrix

Universal Coordinated Time (UTC), in the order year, month, day, hour, minutes, and seconds, for which the function calculates the conversion, specified as one of the following.

- For the year value, enter a double value that is a whole number greater than 1, such as 2013.
- For the month value, enter a double value that is a whole number greater than 0, within the range 1 to 12.
- For the hour value, enter a double value that is a whole number greater than 0, within the range 1 to 24.
- For the hour value, enter a double value that is a whole number greater than 0, within the range 1 to 60.
- For the minute and second values, enter a double value that is a whole number greater than 0, within the range 1 to 60.

Specify these values in one of the following formats:

- 1-by-6 array

Specify a 1-row-by-6-column array of UTC values.

- *M*-by-6 matrix

Specify an M -by-6 array of UTC values, where M is the number of transformation matrices to calculate. Each row corresponds to one set of UTC values.

This is a one row-by-6 column array of UTC values.

Example: [2000 1 12 4 52 12.4]

This is an M -by-6 array of UTC values, where M is 2.

Example: [2000 1 12 4 52 12.4;2010 6 5 7 22 0]

Data Types: double

reduction — Reduction method

'IAU-2000/2006' (default) | 'IAU-76/FK5'

Reduction method to calculate the coordinate conversion, specified as one of the following:

- 'IAU-76/FK5'

Reduce the calculation using the International Astronomical Union (IAU)-76/Fifth Fundamental Catalogue (FK5) (IAU-76/FK5) reference system. Choose this reduction method if the reference coordinate system for the conversion is FK5. You can use the 'dNutation' Name,Value pair with this reduction.

Note This method uses the IAU 1976 precession model and the IAU 1980 theory of nutation to reduce the calculation. This model and theory are no longer current, but the software provides this reduction method for existing implementations. Because of the polar motion approximation that this reduction method uses, `lla2eci` performs a coordinate conversion that is not orthogonal because of the polar motion approximation.

- 'IAU-2000/2006'

Reduce the calculation using the International Astronomical Union (IAU)-2000/2005 reference system. Choose this reduction method if the reference coordinate system for the conversion is IAU-2000. This reduction method uses the P03 precession model to reduce the calculation. You can use the 'dCIP' Name,Value pair with this reduction.

deltaAT — Difference between International Atomic Time and UTC

M -by-1 array of zeroes (default) | scalar | one-dimensional array

Difference between International Atomic Time (IAT) and UTC, in seconds, for which the function calculates the coordinate conversion.

- scalar

Specify one difference-time value to calculate one direction cosine or transformation matrix.

- one-dimensional array

Specify a one-dimensional array with M elements, where M is the number of ECI coordinates. Each row corresponds to one set of ECI coordinates.

Specify 32 seconds as the difference between IAT and UTC.

Example: 32

Data Types: double

deltaUT1 — Difference between UTC and Universal Time (UT1)*M*-by-1 array of zeroes (default) | scalar | one-dimensional array

Difference between UTC and Universal Time (UT1), in seconds, for which the function calculates the coordinate conversion.

- scalar

Specify one difference-time value to calculate ECI coordinates.

- one-dimensional array

Specify a one-dimensional array with *M* elements of difference time values, where *M* is the number of ECI coordinates. Each row corresponds to one set of ECI coordinates.

Specify 0.234 seconds as the difference between UTC and UT1.

Example: 0.234

Data Types: double

polarmotion — Polar displacement*M*-by-2 array of zeroes (default) | 1-by-2 array | *M*-by-2 array

Polar displacement of the Earth, in radians, from the motion of the Earth crust, along the *x*- and *y*-axes.

- 1-by-2 array

Specify a 1-by-2 array of the polar displacement values to convert one ECI coordinate.

- *M*-by-2 array

Specify an *M*-by-2 array of polar displacement values, where *M* is the number of ECI coordinates to convert. Each row corresponds to one set of UTC values.

Example: [-0.0682e-5 0.1616e-5]

Data Types: double

Name-Value Pair Arguments

Specify optional comma-separated pairs of *Name*, *Value* arguments. *Name* is the argument name and *Value* is the corresponding value. *Name* must appear inside quotes. You can specify several name and value pair arguments in any order as *Name1*, *Value1*, ..., *NameN*, *ValueN*.

Example: 'dNutation', [-0.2530e-6 -0.0188e-6]

dNutation — Adjustment to longitude (*dDeltaPsi*) and obliquity (*dDeltaEpsilon*)*M*-by-2 array of zeroes (default) | *M*-by-2 array

Adjustment to the longitude (*dDeltaPsi*) and obliquity (*dDeltaEpsilon*), specified in radians, as the comma-separated pair consisting of *dNutation* and an *M*-by-2 array. You can use this *Name*, *Value* pair with the IAU-76/FK5 reduction.

For historical values, see the International Earth Rotation and Reference Systems Service website (<https://www.iers.org>) and navigate to the Earth Orientation Data Data/Products page.

- *M*-by-2 array

Specify *M*-by-2 array of adjustment values, where *M* is the number of LLA coordinates to be converted. Each row corresponds to one set of longitude and obliquity values.

Data Types: double

dCIP — Adjustment to the location of the celestial intermediate pole (CIP)

M-by-2 array of zeroes (default) | *M*-by-2 array

Adjustment to the location of the Celestial Intermediate Pole (CIP), in radians, specified as the comma-separated pair consisting of *dCIP* and an *M*-by-2 array. This location (*dDeltaX*, *dDeltaY*) is along the *x*- and *y*- axes. You can use this argument with the IAU-200/2006 reduction. By default, this function assumes an *M*-by-2 array of zeroes.

For historical values, see the International Earth Rotation and Reference Systems Service website (<https://www.iers.org>) and navigate to the Earth Orientation Data Data/Products page.

- *M*-by-2 array

Specify *M*-by-2 array of location adjustment values, where *M* is the number of LLA coordinates to be converted. Each row corresponds to one set of *dDeltaX* and *dDeltaY* values.

Example: 'dcip', [-0.2530e-6 -0.0188e-6]

Data Types: double

flattening — Custom ellipsoid planet

1-by-1 array

Custom ellipsoid planet defined by flattening.

Example: 1/290

Data Types: double

re — Custom planet ellipsoid radius

1-by-1 array

Custom planet ellipsoid radius, in meters.

Example: 60000

Data Types: double

See Also

`dcmece2ecef` | `ecef2lla` | `eci2lla` | `geoc2geod` | `geod2geoc` | `lla2ecef`

Introduced in R2014a

lla2flat

Convert from geodetic latitude, longitude, and altitude to flat Earth position

Syntax

```
flatearth_pos = lla2flat(lla, llo, psio, href)
flatearth_pos = lla2flat(lla, llo, psio, href, ellipsoidModel)
flatearth_pos = lla2flat(lla, llo, psio, href, flattening, equatorialRadius)
```

Description

`flatearth_pos = lla2flat(lla, llo, psio, href)` estimates an array of flat Earth coordinates, `flatearth_pos`, from an array of geodetic coordinates, `lla`. This function estimates the `flatearth_pos` value with respect to a reference location that you define with `llo`, `psio`, and `href`.

`flatearth_pos = lla2flat(lla, llo, psio, href, ellipsoidModel)` estimates the coordinates for a specific ellipsoid planet.

`flatearth_pos = lla2flat(lla, llo, psio, href, flattening, equatorialRadius)` estimates the coordinates for a custom ellipsoid planet defined by `flattening` and `equatorialRadius`.

Examples

Estimate Coordinates at Latitude, Longitude, and Altitude

Estimate the coordinates at a latitude, longitude, and altitude:

```
p = lla2flat( [ 0.1 44.95 1000 ], [ 0 45], 5, -100 )
```

```
p =
    1.0e+04 *
    1.0530    -0.6509    -0.0900
```

Estimate Coordinates at Multiple Latitudes, Longitudes, and Altitudes with the WGS84 Ellipsoid Model

Estimate coordinates at multiple latitudes, longitudes, and altitudes with the WGS84 ellipsoid model:

```
p = lla2flat( [ 0.1 44.95 1000; -0.05 45.3 2000 ], [ 0 45], 5, -100, 'WGS84' )
```

```
p =
    1.0e+04 *
```

```

    1.0530   -0.6509   -0.0900
   -0.2597    3.3751   -0.1900

```

Estimate Coordinates at Multiple Latitudes, Longitudes, and Altitudes with a Custom Ellipsoid Model

Estimate coordinates at multiple latitudes, longitudes, and altitudes using a custom ellipsoid model:

```

f = 1/196.877360;
Re = 3397000;
p = lla2flat( [ 0.1 44.95 1000; -0.05 45.3 2000 ], [0 45], 5, -100, f, Re )

p =
    1.0e+04 *
    0.5588   -0.3465   -0.0900
   -0.1373    1.7975   -0.1900

```

Input Arguments

lla — Geodetic coordinates

m-by-3 array

Geodetic coordinates (latitude, longitude, and altitude), specified as an *m*-by-3 array in [degrees degrees meters]. Latitude and longitude values can be any value. However, latitude values of +90 and -90 may return unexpected values because of singularity at the poles.

Data Types: double

llo — Reference location

m-by-2 array

Reference location of latitude and longitude, specified as an *m*-by-2 array, in degrees, for the origin of the estimation and the origin of the flat Earth coordinate system.

Data Types: double

psio — Angular direction of flat Earth

scalar

Angular direction of the flat Earth *x*-axis, specified as a scalar. The angular direction is the degrees clockwise from north, which is the angle in degrees used for converting flat Earth *x* and *y* coordinates to the north and east coordinates.

Data Types: double

href — Reference height

scalar

Reference height from the surface of the Earth to the flat Earth frame with regard to the flat Earth frame, specified as a scalar, in meters.

Data Types: double

ellipsoidModel — Ellipsoid planet model

'WGS84' (default)

Ellipsoid planet model, specified as 'WGS84'.

Data Types: char | string

flattening – Flattening

scalar

Flattening at each pole, specified as a scalar.

Data Types: double

equatorialRadius – Planetary equatorial radius

scalar

Planetary equatorial radius, specified as a scalar, in meters.

Data Types: double

Output Arguments

flatearth_pos – Flat Earth position coordinates

3-element vector

Flat Earth position coordinates, specified as 3-element vector, in meters.

Tips

- This function assumes that the flight path and bank angle are zero.
- This function assumes that the flat Earth z-axis is normal to the Earth only at the initial geodetic latitude and longitude. This function has higher accuracy over small distances from the initial geodetic latitude and longitude. It also has higher accuracy at distances closer to the equator. The function calculates a longitude with higher accuracy when the variations in latitude are smaller. Additionally, longitude is singular at the poles.

Algorithms

The function begins by finding the small changes in latitude and longitude from the output latitude and longitude minus the initial latitude and longitude:

$$d\mu = \mu - \mu_0$$

$$d_l = l - l_0.$$

To convert geodetic latitude and longitude to the north and east coordinates, the function uses the radius of curvature in the prime vertical (R_N) and the radius of curvature in the meridian (R_M). R_N and R_M are defined by the following relationships:

$$R_N = \frac{R}{\sqrt{1 - (2f - f^2)\sin^2\mu_0}},$$

where (R) is the equatorial radius of the planet and f is the flattening of the planet.

Small changes in the north (dN) and east (dE) positions are approximated from small changes in the north and east positions by

$$dN = \frac{d\mu}{\operatorname{atan}\left(\frac{1}{R_M}\right)},$$

and

$$dE = \frac{d\mu}{\operatorname{atan}\left(\frac{1}{R_N \cos \mu_0}\right)}.$$

With the conversion of the North and East coordinates to the flat Earth x and y coordinates, the transformation has the form of

$$\begin{bmatrix} p_x \\ p_y \end{bmatrix} = \begin{bmatrix} \cos \psi & \sin \psi \\ -\sin \psi & \cos \psi \end{bmatrix} \begin{bmatrix} N \\ E \end{bmatrix},$$

where

(ψ)

is the angle in degrees clockwise between the x -axis and north.

The flat Earth z -axis value is the negative altitude minus the reference height (h_{ref}):

$$p_z = -h - h_{ref}.$$

References

[1] Etkin, B., *Dynamics of Atmospheric Flight*. New York: John Wiley & Sons, 1972.

See Also

Topics

flat2lla

Introduced in R2011a

load (Aero.Body)

Get geometry data from source

Syntax

```
load(h, bodyDataSrc)
h.load(bodyDataSrc)
load(h, bodyDataSrc, geometrystate)
h.load(bodyDataSrc, geometrystate)
```

Description

`load(h, bodyDataSrc)` and `h.load(bodyDataSrc)` load the graphics data from the body graphics file. This command assumes a default geometry source type set to `Auto`.

`load(h, bodyDataSrc, geometrystate)` and `h.load(bodyDataSrc, geometrystate)` load the graphics data from the body graphics file, `bodyDataSrc`, into the face, vertex, and color data of the animation body object `h`. Then, when axes `ax` is available, you can use this data to generate patches with `generatePatches`. `geometrystate` is the geometry source type for the body.

By default `geometrystate` is set to `Auto`, which recognizes `.mat` extensions as MAT-files, `.ac` extensions as Ac3d files, and structures containing fields of `name`, `faces`, `vertices`, and `cdata` as MATLAB variables. If you want to use alternate file extensions or file types, enter one of the following:

- `Auto`
- `Variable`
- `MatFile`
- `Ac3d`
- `Custom`

Examples

Load the graphic data from the graphic data file, `pa24-250_orange.ac`, into `b`.

```
b=Aero.Body;
b.load('pa24-250_orange.ac','Ac3d');
```

See Also

`generatePatches` | `move` | `update`

Introduced in R2007a

machnumber

Compute Mach number using velocity and speed of sound

Syntax

```
mach = machnumber(velocities,speed_of_sound)
```

Description

`mach = machnumber(velocities,speed_of_sound)` computes Mach numbers, `mach`, from an m -by-3 array of Cartesian velocity vectors, `velocities`, and an array of m speeds of sound, `speed_of_sound`.

Examples

Determine Mach Number for Velocity and Speed of Sound in Feet per Second

Determine the Mach number for velocity and speed of sound in feet per second:

```
mach = machnumber([84.3905 33.7562 10.1269], 1116.4505)
```

```
mach =  
    0.0819
```

Determine Mach Number for Velocity and Speed of Sound in Meters per Second

Determine the Mach number for velocity and speed of sound in meters per second:

```
mach = machnumber([25.7222 10.2889 3.0867], [340.2941 295.0696])
```

```
mach =  
    0.0819    0.0945
```

Determine Mach Number for Velocity and Speed of Sound in Knots

Determine the Mach number for velocity and speed of sound in knots:

```
mach = machnumber([50 20 6; 5 0.5 2], [661.4789 573.5694])
```

```
mach =
```



```
0.0819  
0.0094
```

Input Arguments

velocities — Cartesian velocity vectors

m-by-3 array | vector

Cartesian velocity vectors, specified as an *m*-by-3 array. `velocities` and `speed_of_sound` must have the same length.

Data Types: double

speed_of_sound — Speed of sound

array

Speed of sound, specified as an array of *m* speeds of sound. `velocities` and `speed_of_sound` must have the same length.

Data Types: double

Output Arguments

mach — Mach numbers

scalar | array

Mach numbers, returned as a scalar or array of *m* Mach numbers.

See Also

`airspeed` | `alphabeta` | `dpressure`

Introduced in R2006b

mjuliandate

Modified Julian date calculator

Syntax

```
mjd = mjuliandate(dateVector)
mjd = mjuliandate(dateCharacterVector, format)
mjd = mjuliandate(year, month, day)
dy = mjuliandate([year, month, day])
mjd = mjuliandate(year, month, day, hour, minute, second)
dy = mjuliandate([year, month, day, hour, minute, second])
```

Description

`mjd = mjuliandate(dateVector)` converts one or more date vectors, `dateVector`, to modified Julian date, `mjd`. Modified Julian dates begin at midnight rather than noon, and the first two digits of its corresponding Julian date are removed.

`mjd = mjuliandate(dateCharacterVector, format)` converts one or more date character vectors, `dateCharacterVector`, to modified Julian date, `mjd`, using format `format`.

`mjd = mjuliandate(year, month, day)` and `dy = mjuliandate([year, month, day])` return the modified Julian date for corresponding elements of the `year`, `month`, `day` arrays.

`mjd = mjuliandate(year, month, day, hour, minute, second)` and `dy = mjuliandate([year, month, day, hour, minute, second])` return the modified Julian date for corresponding elements of the `year`, `month`, `day`, `hour`, `minute`, `second` arrays. Specify the six arguments as one-dimensional arrays of the same length or scalar values.

Examples

Calculate Modified Julian Date Using Date Character Version and dd-mm-yyyy Format

Calculate the modified Julian date for May 24, 2005 using date character version and dd-mm-yyyy format:

```
mjd = mjuliandate('24-May-2005', 'dd-mmm-yyyy')
```

```
mjd =  
    53514
```

Calculate Modified Julian Date Using Year, Month, and Day Inputs

Calculate modified Julian date for December 19, 2006 from year, month, and day inputs:

```
mjd = mjuliandate(2006, 12, 19)
```

```
mjd =
    54088
```

Calculate Modified Julian Date Using Year, Month, Day, Hour, Minute, and Second Inputs

Calculate the modified Julian date for October 10, 2004, at 12:21:00 p.m. using year, month, day, hour, month, and second inputs:

```
mjd = mjuliandate(2004,10,10,12,21,0)
```

```
mjd =
    5.3289e+004
```

Input Arguments

dateVector — Full or partial date vector

m-by-6 matrix | *m*-by-3 matrix | positive double-precision number

Full or partial date vector, specified as an *m*-by-6 or *m*-by-3 matrix containing *m* full or partial date vectors, respectively:

- Full date vector — Contains six elements specifying the year, month, day, hour, minute, and second
- Partial date vector — Contains three elements specifying the year, month, and day

Data Types: double

dateCharacterVector — Date character vector

character array | one-dimensional cell array of character vectors

Date character vector, specified as a character array, where each row corresponds to one date, or a one-dimensional cell array of character vectors.

Data Types: char | string

format — Date format

-1 (default) | character vector | string scalar | integer

Date format, specified as a character vector, string scalar, or integer. All dates in `dateCharacterVector` must have the same format and use the same date format symbols as the `datenum` function.

`mjuliandate` does not accept formats containing the letter *Q*.

If the format does not contain enough information to compute a date number, then:

- Hours, minutes, and seconds default to 0.
- Days default to 1.
- Months default to January.
- Years default to the current year.

Data Types: char | string

year — Year

current year (default) | scalar | one-dimensional array

Year, specified as a scalar or one-dimensional array.

Dates with two character years are interpreted to be within 100 years of the current year.

Dependencies

Depending on the syntax, specify **year**, **month**, and **day** or **year**, **month**, **day**, **hour**, **minute**, and **second** as one-dimensional arrays of the same length or scalar values.

Data Types: char | string

month — Month

1 (default) | 2 | 3 | 4 | 5 | 6 | 7 | 8 | 9 | 10 | 11 | 12 | one-dimensional array

Month, specified as a scalar or one-dimensional array from 1 to 12.

Dependencies

Depending on the syntax, specify **year**, **month**, and **day** or **year**, **month**, **day**, **hour**, **minute**, and **second** as one-dimensional arrays of the same length or scalar values.

Data Types: double

day — Day

1 (default) | 2 | 3 | 4 | 5 | 6 | 7 | 8 | 9 | 10 | 11 | 12 | 13 | 14 | 15 | 16 | 17 | 18 | 19 | 20 | 21 | 22 | 23 | 24 | 25 | 26 | 27 | 28 | 29 | 30 | 31 | one-dimensional array

Day, specified as a scalar or one-dimensional array from 1 to 31.

Dependencies

Depending on the syntax, specify **year**, **month**, and **day** or **year**, **month**, **day**, **hour**, **minute**, and **second** as one-dimensional arrays of the same length or scalar values.

Data Types: double

hour — Date format

0 (default) | double, whole number, 0 to 24

Hour, specified as a scalar from 0 to 24.

Dependencies

Depending on the syntax, specify **year**, **month**, and **day** or **year**, **month**, **day**, **hour**, **minute**, and **second** as one-dimensional arrays of the same length or scalar values.

Data Types: double

minute — Minute

0 (default) | double, whole number, 0 to 60

Minute, specified as a double, whole number from 0 to 60.

Dependencies

Depending on the syntax, specify **year**, **month**, and **day** or **year**, **month**, **day**, **hour**, **minute**, and **second** as one-dimensional arrays of the same length or scalar values.

Data Types: double

second — Second

0 (default) | double, whole number, 0 to 60

Second, specified as a double, whole number from 0 to 60.

Dependencies

Depending on the syntax, specify year, month, and day or year, month, day, hour, minute, and second as one-dimensional arrays of the same length or scalar values.

Data Types: double

Output Arguments

mjd — Modified Julian date

m-by-6 column vector | *m*-by-3 column vector

Modified Julian date, returned as a column vector of *m* modified Julian dates, which are the number of days and fractions since noon Universal Time on January 1, 4713 BCE.

- *m*-by-6 column vector — Contains six elements specifying the year, month, day, hour, minute, and second
- *m*-by-3 column vector — Contains three elements specifying the year, month, and day

Dependencies

The output format depends on the input format:

Input Syntax	dy Format
<code>mjd = mjuliandate(dateVector)</code>	<i>m</i> -by-6 column vector or <i>m</i> -by-3 column vector of <i>m</i> modified Julian dates.
<code>mjd = mjuliandate(dateCharacterVector, format)</code>	Column vector of <i>m</i> modified Julian dates, where <i>m</i> is the number of character vectors in <code>dateCharacterVector</code> .

Limitations

The calculation of modified Julian date does not take into account leap seconds.

See Also

`datenum` | `datestr` | `decyear` | `juliandate` | `leapyear`

Introduced in R2006b

moonLibration

Moon librations

Syntax

```
angles= moonLibration(ephemerisTime)
angles= moonLibration(ephemerisTime,ephemerisModel)
angles= moonLibration(ephemerisTime,ephemerisModel,action)
```

```
[angles,rates] = moonLibration( ___ )
```

Description

`angles= moonLibration(ephemerisTime)` implements the Moon libration angles for `ephemerisTime`, expressed in Julian days.

The function uses the Chebyshev coefficients that the NASA Jet Propulsion Laboratory provides.

This function requires that you download ephemeris data with the Add-On Explorer. For more information, see `aeroDataPackage`.

`angles= moonLibration(ephemerisTime,ephemerisModel)` uses the `ephemerisModel` coefficients to implement these values.

`angles= moonLibration(ephemerisTime,ephemerisModel,action)` uses `action` to determine error reporting.

`[angles,rates] = moonLibration(___)` implements the Moon libration angles and rates using any combination of the input arguments in the previous syntaxes.

Examples

Implement Libration Angles of Moon

Implement libration angles of the Moon for December 1, 1990 with DE405. Use the `juliandate` function to calculate the input Julian date value.

```
angles = moonLibration(juliandate(1990,12,1))
```

```
angles =
    1.0e+03 *
    0.0001    0.0004    1.8010
```

Implement Libration Angles and Rates for Moon

Specify the ephemerides (DE421) and use the `juliandate` function for the date (January 1, 2000) to calculate both the Moon libration angles and rates.

```
[angles,rates] = moonLibration([2451544.5 0.5], '421')
```

```

angles =
  1.0e+03 *
  -0.0001    0.0004    2.5643

rates =
  -0.0001    0.0000    0.2301

```

Input Arguments

ephemerisTime — Julian dates

scalar | 2-element vector | column vector | M -by-2 matrix

Julian dates for which the positions are calculated, specified as one of the following:

- Scalar
 - Specify one fixed Julian date.
- 2-element vector
 - Specify the Julian date in multiple parts. The first element is the Julian date for a specific epoch that is the most recent midnight at or before the interpolation epoch. The second element is the fractional part of a day elapsed between the first element and epoch. The second element must be positive. The value of the first element plus the second element cannot exceed the maximum Julian date.
- Column vector
 - Specify a column vector with M elements, where M is the number of Julian dates.
- M -by-2 matrix
 - Specify a matrix, where M is the number of Julian dates and the second column contains the elapsed days (Julian epoch date/elapsed day pairs).

Data Types: double

ephemerisModel — Ephemerides coefficients

'405' (default) | '421' | '423' | '430' | '432t'

Ephemerides coefficients, specified as one of these ephemerides defined by the Jet Propulsion Laboratory:

- '405'
 - Released in 1998. This ephemerides takes into account the Julian date range 2305424.50 (December 9, 1599) to 2525008.50 (February 20, 2201).
 - This function calculates these ephemerides with respect to the International Celestial Reference Frame version 1.0, adopted in 1998.
- '421'
 - Released in 2008. This ephemerides takes into account the Julian date range 2414992.5 (December 4, 1899) to 2469808.5 (January 2, 2050).
 - This function calculates these ephemerides with respect to the International Celestial Reference Frame version 1.0, adopted in 1998.

- '423'

Released in 2010. This ephemerides takes into account the Julian date range 2378480.5 (December 16, 1799) to 2524624.5 (February 1, 2200).

This function calculates these ephemerides with respect to the International Celestial Reference Frame version 2.0, adopted in 2010.

- '430'

Released in 2013. This ephemerides takes into account the Julian date range 2287184.5 (December 21, 1549) to 2688976.5 (January 25, 2650).

This function implements these ephemerides with respect to the International Celestial Reference Frame version 2.0, adopted in 2010.

- '432t'

Released in April 2014. This ephemerides takes into account the Julian date range 2287184.5, (December 21, 1549) to 2688976.5, (January 25, 2650).

This function implements these ephemerides with respect to the International Celestial Reference Frame version 2.0, adopted in 2010.

Data Types: char

action — Function behavior

'Error' (default) | 'None' | 'Warning'

Function behavior when inputs are out of range, specified as one of these values:

Value	Description
'None'	No action.
'Warning'	Warning in the MATLAB Command Window, model simulation continues.
'Error'	MATLAB returns an exception, model simulation stops.

Data Types: char

Output Arguments

angles — Moon libration angles

M-by-3 numeric array

Moon libration angles, specified as an *M*-by-3 numeric array. *M* is the number of Julian dates, in rows. The columns contain the Euler angles (φ θ ψ) for Moon attitude, in radians.

If the input arguments include multiple Julian dates or epochs, this array has the same number of rows as the `ephemerisTime` input.

rates — Moon libration angular rates

M-by-3 numeric array

Moon libration angular rates, specified as an *M*-by-3 numeric array. *M* is the number of Julian dates, in rows. The columns contain the Moon libration Euler angular rates (ω), in radians/day.

If the input arguments include multiple Julian dates or epochs, this array has the same number of rows as the `ephemerisTime` input.

References

- [1] Folkner, W. M., J. G. Williams, D. H. Boggs, "The Planetary and Lunar Ephemeris DE 421," *JPL Interplanetary Network Progress Report 24-178*, 2009.
- [2] Vallado, D. A., *Fundamentals of Astrodynamics and Applications*, McGraw-Hill, New York, 1997.
- [3] Folkner, W. M. "Recent Developments in Planetary Ephemeris Observations." California Institute of Technology, Pasadena, California, 2010.

See Also

`earthNutation` | `juliandate` | `planetEphemeris`

External Websites

https://ssd.jpl.nasa.gov/?planet_eph_export

Introduced in R2013a

move (Aero.Body)

Change animation body position and orientation

Syntax

```
move(h, translation, rotation)
h.move(translation, rotation)
```

Description

`move(h, translation, rotation)` and `h.move(translation, rotation)` set a new position and orientation for the body object `h`. `translation` is a 1-by-3 matrix in the aerospace body x - y - z coordinate system. `rotation` is a 1-by-3 matrix, in radians, that specifies the rotations about the right-hand x - y - z sequence of coordinate axes. The order of application of the rotation is z - y - x (r - q - p).

Examples

Change animation body position to *newpos* and *newrot*.

```
h = Aero.Body;
h.load('ac3d_xyzisrgb.ac', 'Ac3d');
newpos = h.Position + 1.00;
newrot = h.Rotation + 0.01;
h.move(newpos, newrot);
```

See Also

load

Introduced in R2007a

move (Aero.Node)

Change node translation and rotation

Syntax

```
move(h,translation,rotation)
h.move(translation,rotation)
```

Description

`move(h,translation,rotation)` and `h.move(translation,rotation)` set a new position and orientation for the node object `h`. `translation` is a 1-by-3 matrix in the aerospace body x - y - z coordinate system or another coordinate system. In the latter case, you can use the `CoordTransformFcn` function to move it into an aerospace body. The defined aerospace body coordinate system is defined relative to the screen as x -left, y -in, z -down.

`rotation` is a 1-by-3 matrix, in radians, that specifies the rotations about the right-hand x - y - z sequence of coordinate axes. The order of application of the rotation is z - y - x (r - q - p). This function uses the `CoordTransformFcn` to apply the translation and rotation from the input coordinate system to the aerospace body. The function then moves the translation and rotation from the aerospace body to the VRML x - y - z coordinates. The defined VRML coordinate system is defined relative to the screen as x -right, y -up, z -out.

Examples

Move the Lynx body. This example uses the Simulink 3D Animation `vrnode/getfield` function to retrieve the translation and rotation. These coordinates are those used in the Simulink 3D Animation software.

```
h = Aero.VirtualRealityAnimation;
h.VRWorldFilename = [matlabroot,'/toolbox/aero/astdemos/asttkoff.wrl'];
copyfile(h.VRWorldFilename,[tempdir,'asttkoff.wrl'],'f');
h.VRWorldFilename = [tempdir,'asttkoff.wrl'];
h.initialize();
newtrans = getfield(h.Nodes{4}.VRNode,'translation') + 1.0;
newrot = getfield(h.Nodes{4}.VRNode,'rotation') + [.2 0.01 0.01 0.01];
h.Nodes{4}.move(newtrans,newrot);
```

Limitations

This function cannot get the node position in aerospace body coordinates; it needs to use the `CoordTransformFcn` to do so.

This function cannot set a viewpoint position or orientation (see `addViewpoint`).

See Also

`addNode`

Introduced in R2007b

moveBody

Class: Aero.Animation

Package: Aero

Move body in animation object

Syntax

```
moveBody(h,idx,translation,rotation)
h.moveBody(idx,translation,rotation)
```

Description

`moveBody(h,idx,translation,rotation)` and `h.moveBody(idx,translation,rotation)` set a new position and attitude for the body specified with the index `idx` in the animation object `h`. `translation` is a 1-by-3 matrix in the aerospace body coordinate system. `rotation` is a 1-by-3 matrix, in radians, that specifies the rotations about the right-hand x - y - z sequence of coordinate axes. The order of application of the rotation is z - y - x (R - Q - P).

Input Arguments

<code>h</code>	Animation object.
<code>translation</code>	1-by-3 matrix in the aerospace body coordinate system.
<code>rotation</code>	1-by-3 matrix, in radians, that specifies the rotations about the right-hand x - y - z sequence of coordinate axes.
<code>idx</code>	Body specified with this index.

Examples

Move the body with the index 1 to position offset from the original by $+ [0 \ 0 \ -3]$ and rotation, `rot1`.

```
h = Aero.Animation;
idx1 = h.createBody('pa24-250_orange.ac','Ac3d');
pos1 = h.Bodies{1}.Position;
rot1 = h.Bodies{1}.Rotation;
h.moveBody(1,pos1 + [0 0 -3],rot1);
```

Node (Aero.Node)

Create node object for use with virtual reality animation

Syntax

```
h = Aero.Node
```

Description

`h = Aero.Node` creates a node object for use with virtual reality animation.

See `Aero.Node` for further details.

See Also

`Aero.Node`

Introduced in R2007b

nodeInfo (Aero.VirtualRealityAnimation)

Create list of nodes associated with virtual reality animation object

Syntax

```
nodeInfo(h)  
h.nodeInfo  
n = nodeInfo(h)  
n = h.nodeInfo
```

Description

`nodeInfo(h)` and `h.nodeInfo` create a list of nodes associated with the virtual reality animation object, `h`.

`n = nodeInfo(h)` and `n = h.nodeInfo` create a cell array (`n`) that contains the node information. The function stores the information in a cell array as follows:

```
N{1,n} = Node Index  
N{2,n} = Node Name  
N{3,n} = Node Type
```

where `n` is the number of nodes. You might want to use this function to find an existing node by name and then perform a certain action on it using the node index.

Examples

Create list of nodes associated with virtual reality animation object, `h`.

```
h = Aero.VirtualRealityAnimation;  
h.VRWorldFilename = [matlabroot,'/toolbox/aero/astdemos/asttkoff.wrl'];  
h.initialize();  
h.nodeInfo;
```

See Also

`addNode`

Introduced in R2007b

nonlinearDynamics

Class: Aero.FixedWing

Package: Aero

Calculate dynamics of fixed-wing aircraft

Syntax

```
state_derivatives = nonlinearDynamics(aircraft, state)
```

Description

`state_derivatives = nonlinearDynamics(aircraft, state)` returns the column vector of `state_derivatives` of the fixed-wing aircraft `aircraft` from the initial state `state`.

Input Arguments

aircraft — Aero.FixedWing object

scalar

Aero.FixedWing object, specified as a scalar.

state — Aero.FixedWing.State object

scalar

Aero.FixedWing.State specified as a scalar.

Output Arguments

state_derivatives — State derivatives

vector

State derivatives with respect to time, returned as a vector. The rate vector size depends on the degrees of freedom, and is defined in the following form:

4th order **point mass**:

```
DYDT(1) = dXN/dt
DYDT(2) = dXD/dt
DYDT(3) = dU/dt
DYDT(4) = dW/dt
```

6th order **point mass**:

```
DYDT(1) = dXN/dt
DYDT(2) = dXE/dt
DYDT(3) = dXD/dt
DYDT(4) = dU/dt
DYDT(5) = dV/dt
DYDT(6) = dW/dt
```

3 DOF:

```
DYDT(1) = dXN/dt
DYDT(2) = dXD/dt
DYDT(3) = dU/dt
DYDT(4) = dW/dt
DYDT(5) = dQ/dt
DYDT(6) = dTheta/dt
```

6 DOF:

```
DYDT(1) = dXN/dt
DYDT(2) = dXE/dt
DYDT(3) = dXD/dt
DYDT(4) = dU/dt
DYDT(5) = dV/dt
DYDT(6) = dW/dt
DYDT(7) = dP/dt
DYDT(8) = dQ/dt
DYDT(9) = dR/dt
DYDT(10) = dPhi/dt
DYDT(11) = dTheta/dt
DYDT(12) = dPsi/dt
```

Examples

Calculate Dynamics of a Cessna 182:

Calculate the dynamics of Cessna 182.

```
[C182, CruiseState] = astC182();
dydt = nonlinearDynamics(C182, CruiseState)
```

dydt =

```
220.1000
    0
    0
-2.8323
    0
-0.0040
    0
 1.3922
    0
    0
    0
    0
```

Limitations

When used with `Simulink.LookupTable` objects, this method requires a Simulink license.

See Also

`Aero.FixedWing` | `forcesAndMoments` | `linearize`

Introduced in R2021a

orbitalElements

Package: satelliteScenario

Orbital elements of satellites in scenario

Syntax

```
elements = orbitalElements(sat)
```

Description

`elements = orbitalElements(sat)` returns the orbital elements of the specified satellite `sat`.

Input Arguments

sat – Satellite

row vector of `Satellite` objects

Satellite, specified as a row vector of `Satellite` objects.

Output Arguments

elements – Orbital elements

structure

Orbital elements of input `sat`, returned as a structure. The fields of the structure depend on the orbit propagator chosen using the `OrbitPropagator` property of the `satelliteScenario` object.

Two Body Keplerian

The two-body-keplerian orbit propagator has these fields:

- `SemiMajorAxis`
- `Eccentricity`
- `Inclination`
- `RightAscensionOfAscendingNode`
- `ArgumentOfPeriapsis`
- `TrueAnomaly`
- `Period`

SGP4 and SDP4

The `sgp4` and `sdp4` orbit propagators have these fields:

- `Eccentricity`
- `Inclination`
- `RightAscensionOfAscendingNode`

- ArgumentOfPeriapsis
- MeanAnomaly
- MeanMotion
- Epoch
- BStar
- Period

The orbital elements represent the mean values at Epoch.

Ephemeris

The ephemeris propagator has these fields:

- EphemerisStartTime
- EphemerisStopTime
- PositionTimeTable
- VelocityTimeTable

See Also

Objects

satelliteScenario | satelliteScenarioViewer

Functions

access | conicalSensor | groundStation | play | satellite | show

Topics

“Satellite Scenario Key Concepts” on page 2-61

Introduced in R2021a

planetEphemeris

Position and velocity of astronomical objects

Syntax

```
position= planetEphemeris(ephemerisTime,center,target)
position = planetEphemeris(ephemerisTime,center,target,ephemerisModel)
position = planetEphemeris(ephemerisTime,center,target,ephemerisModel,units)
position= planetEphemeris(ephemerisTime,center,target,ephemerisModel,units,
action)
```

```
[position,velocity] = planetEphemeris( ___ )
```

Description

`position= planetEphemeris(ephemerisTime,center,target)` implements the position of the target object relative to the specified center object for a given Julian date `ephemerisTime`. By default, the function implements the position based on the DE405 ephemerides in units of km.

The function uses the Chebyshev coefficients that the NASA Jet Propulsion Laboratory provides.

This function requires that you download ephemeris data with the Add-On Explorer. For more information, see `aeroDataPackage`.

`position = planetEphemeris(ephemerisTime,center,target,ephemerisModel)` uses the `ephemerisModel` coefficients to implement these values.

`position = planetEphemeris(ephemerisTime,center,target,ephemerisModel,units)` specifies the units for these values.

`position= planetEphemeris(ephemerisTime,center,target,ephemerisModel,units,action)` uses `action` to determine error reporting.

`[position,velocity] = planetEphemeris(___)` implements the position and velocity of a the target object relative to the specified center for a given Julian date `ephemerisTime` using any of the input arguments in the previous syntaxes.

Examples

Implement Position of Moon

Implement the position of the Moon with respect to the Earth for December 1, 1990 with DE405:

```
position = planetEphemeris(juliandate(1990,12,1),'Earth','Moon')
```

```
position =
    1.0e+05 *
    2.3112    2.3817    1.3595
```

Implement Position and Velocity for Saturn

Implement the position and velocity for Saturn with respect to the Solar System barycenter for noon on January 1, 2000 using DE421 and AU units:

```
[position,velocity] = planetEphemeris([2451544.5 0.5],...
'SolarSystem','Saturn','421','AU')

position =
    6.3993    6.1720    2.2738
velocity =
   -0.0043    0.0035    0.0016
```

Input Arguments

ephemerisTime — Julian date

scalar | 2-element vector | column vector | M -by-2 matrix

Julian date for which the positions are calculated, specified as one of the following:

- Scalar

Specify one fixed Julian date.

- 2-element vector

Specify the Julian date in multiple parts. The first element is the Julian date for a specific epoch that is the most recent midnight at or before the interpolation epoch. The second element is the fractional part of a day elapsed between the first element and epoch. The second element must be positive. The value of the first element plus the second element cannot exceed the maximum Julian date.

- Column vector

Specify a column vector with M elements, where M is the number of fixed Julian dates.

- M -by-2 matrix

Specify a matrix, where M is the number of Julian dates and the second column contains the elapsed days (Julian epoch date/elapsed day pairs).

Data Types: double

center — Reference body (astronomical object) or point of reference

'Sun' | 'Mercury' | 'Venus' | 'Earth' | 'Moon' | 'Mars' | 'Jupiter' | 'Saturn' | 'Uranus' | 'Neptune' | 'Pluto' | 'SolarSystem' | 'EarthMoon'

Reference body (astronomical object) or point of reference from which to measure the target barycenter position and velocity.

Data Types: char

target — Target body (astronomical object) or point of reference

'Sun' | 'Mercury' | 'Venus' | 'Earth' | 'Moon' | 'Mars' | 'Jupiter' | 'Saturn' | 'Uranus' | 'Neptune' | 'Pluto' | 'SolarSystem' | 'EarthMoon'

Target body (astronomical object) or point of reference of the barycenter position and velocity measurement.

Data Types: char

ephemerisModel — Ephemerides coefficients

'405' (default) | '421' | '423' | '430' | '432t'

Ephemerides coefficients, specified as one of these ephemerides defined by the Jet Propulsion Laboratory:

- '405'

Released in 1998. This ephemerides takes into account the Julian date range 2305424.50 (December 9, 1599) to 2525008.50 (February 20, 2201).

This function calculates these ephemerides with respect to the International Celestial Reference Frame version 1.0, adopted in 1998.

- '421'

Released in 2008. This ephemerides takes into account the Julian date range 2414992.5 (December 4, 1899) to 2469808.5 (January 2, 2050).

This function calculates these ephemerides with respect to the International Celestial Reference Frame version 1.0, adopted in 1998.

- '423'

Released in 2010. This ephemerides takes into account the Julian date range 2378480.5 (December 16, 1799) to 2524624.5 (February 1, 2200).

This function calculates these ephemerides with respect to the International Celestial Reference Frame version 2.0, adopted in 2010.

- '430'

Released in 2013. This ephemerides takes into account the Julian date range 2287184.5 (December 21, 1549) to 2688976.5 (January 25, 2650).

This function implements these ephemerides with respect to the International Celestial Reference Frame version 2.0, adopted in 2010.

- '432t'

Released in April 2014. This ephemerides takes into account the Julian date range 2287184.5, (December 21, 1549) to 2688976.5, (January 25, 2650).

This function implements these ephemerides with respect to the International Celestial Reference Frame version 2.0, adopted in 2010.

Data Types: char

units — Output units

'km' (default) | 'AU'

Output units for position and velocity, specified as 'km' for km and km/s or 'AU' for astronomical units or AU/day.

Data Types: char

action – Function behavior

'Error' (default) | 'None' | 'Warning'

Function behavior when inputs are out of range.

Value	Description
'None'	No action.
'Warning'	Warning in the MATLAB Command Window, model simulation continues.
'Error'	MATLAB returns an exception, model simulation stops.

Data Types: char

Output Arguments**position – Barycenter position***M*-by-3 vector

Barycenter position of the `target` object relative to the barycenter of the `center` object, returned as an *M*-by-3 vector, where *M* is the number of Julian dates. The 3 vector contains the *x*, *y*, and *z* of the position along the International Celestial Reference Frame (ICRF). Units are km or astronomical units (AU). If input arguments include multiple Julian dates or epochs, this vector has the same number of rows as the `ephemerisTime` input.

velocity – Barycenter velocity*M*-by-3 vector

Barycenter velocity of the `target` object relative to the barycenter of the `center` object, returned as an *M*-by-3 vector, where *M* is the number of Julian dates. The 3 vector contains the velocity in the *x*, *y*, and *z* directions along the ICRF. Velocity of the Units are km or astronomical units (AU). If the input includes multiple Julian dates or epochs, this vector has the same number of rows as the `ephemerisTime` input.

References

- [1] Folkner, W. M., J. G. Williams, D. H. Boggs, "The Planetary and Lunar Ephemeris DE 421," *JPL Interplanetary Network Progress Report 24-178*, 2009.
- [2] Ma, C. et al., "The International Celestial Reference Frame as Realized by Very Long Baseline Interferometry," *Astronomical Journal*, Vol. 116, 516-546, 1998.
- [3] Vallado, D. A., *Fundamentals of Astrodynamics and Applications*, McGraw-Hill, New York, 1997.

See Also

earthNutation | juliandate | moonLibration

Topics

"Estimate Sun Analemma Using Planetary Ephemerides and ECI to AER Transformation" on page 5-108

"Marine Navigation Using Planetary Ephemerides" on page 5-99

External Websites

https://ssd.jpl.nasa.gov/?planet_eph_export

Introduced in R2013a

play

Class: Aero.Animation

Package: Aero

Animate Aero.Animation object given position/angle time series

Syntax

```
play(h)
h.play
```

Description

`play(h)` and `h.play` animate the loaded geometry in `h` for the current `TimeseriesDataSource` at the specified rate given by the `'TimeScaling'` property (in seconds of animation data per second of wall-clock time) and animated at a certain number of frames per second using the `'FramesPerSecond'` property.

The time series data is interpreted according to the `'TimeseriesSourceType'` property, which can be one of:

<code>'Timeseries'</code>	MATLAB time series data with six values per time: <code>x y z phi theta psi</code> The values are resampled.
<code>'Simulink.Timeseries'</code>	Simulink.Timeseries (Simulink signal logging): <ul style="list-style-type: none"> • First data item <code>x y z</code> • Second data item <code>phi theta psi</code>
<code>'StructureWithTime'</code>	Simulink struct with time (for example, Simulink root output logging <code>'Structure with time'</code>): <ul style="list-style-type: none"> • <code>signals(1).values: x y z</code> • <code>signals(2).values: phi theta psi</code> Signals are linearly interpolated vs. time using <code>interp1</code> .
<code>'Array6DoF'</code>	A double-precision array in <code>n</code> rows and 7 columns for 6-DoF data: <code>time x y z phi theta psi</code> . If a double-precision array of 8 or more columns is in <code>'TimeseriesSource'</code> , the first 7 columns are used as 6-DoF data.

'Array3DoF'	A double-precision array in n rows and 4 columns for 3-DoF data: time x z theta. If a double-precision array of 5 or more columns is in 'TimeseriesSource', the first 4 columns are used as 3-DoF data.
'Custom'	Position and angle data is retrieved from 'TimeseriesSource' by the currently registered 'TimeseriesReadFcn'.

The following are limitations for the TStart and TFinal values:

- TStart and TFinal must be numeric.
- TStart and TFinal cannot be Inf or NaN.
- TFinal must be greater than or equal to TStart.
- TFinal cannot be greater than the maximum Timeseries time.
- TStart cannot be less than the minimum Timeseries time.

The time advancement algorithm used by play is based on animation frames counted by ticks:

```
ticks = ticks + 1;
time = tstart + ticks*FramesPerSecond*TimeScaling;
```

where

TimeScaling	Specify the seconds of animation data per second of wall-clock time.
FramesPerSecond	Specify the number of frames per second used to animate the 'TimeseriesSource'.

For default 'TimeseriesReadFcn' methods, the last frame played is the last time value.

Time is in seconds, position values are in the same units as the geometry data loaded into the animation object, and all angles are in radians.

Note If there is a 15% difference between the expected time advance and the actual time advance, this method will generate the following warning:

```
TimerPeriod has been set to <value>. You may wish to modify the animation
TimeScaling and FramesPerSecond properties to compensate for the
millisecond limit of the TimerPeriod. See documentation for details.
```

Input Arguments

h Animation object.

Examples

Animate the body, idx1, for the duration of the time series data.

```
h = Aero.Animation;
h.FramesPerSecond = 10;
h.TimeScaling = 5;
idx1 = h.createBody('pa24-250_orange.ac', 'Ac3d');
```

```
load simdata;  
h.Bodies{1}.TimeSeriesSource = simdata;  
h.show();  
h.play();
```

play (Aero.FlightGearAnimation)

Animate FlightGear flight simulator using given position/angle time series

Syntax

```
play(h)
h.play
```

Description

`play(h)` and `h.play` animate FlightGear flight simulator using specified time series data in `h`. The time series data can be set in `h` by using the property `'TimeseriesSource'`.

The time series data, stored in the property `'TimeseriesSource'`, is interpreted according to the `'TimeseriesSourceType'` property, which can be one of:

<code>'Timeseries'</code>	MATLAB time series data with six values per time: latitude longitude altitude phi theta psi The values are resampled.
<code>'StructureWithTime'</code>	Simulink struct with time (for example, Simulink root outport logging <code>'Structure with time'</code>): <ul style="list-style-type: none"> <code>signals(1).values</code>: latitude longitude altitude <code>signals(2).values</code>: phi theta psi Signals are linearly interpolated vs. time using <code>interp1</code> .
<code>'Array6DoF'</code>	A double-precision array in <code>n</code> rows and 7 columns for 6-DoF data: time latitude longitude altitude phi theta psi. If a double-precision array of 8 or more columns is in <code>'TimeseriesSource'</code> , the first 7 columns are used as 6-DoF data.
<code>'Array3DoF'</code>	A double-precision array in <code>n</code> rows and 4 columns for 3-DoF data: time latitude altitude theta. If a double-precision array of 5 or more columns is in <code>'TimeseriesSource'</code> , the first 4 columns are used as 3-DoF data.
<code>'Custom'</code>	Position and angle data is retrieved from <code>'TimeseriesSource'</code> by the currently registered <code>'TimeseriesReadFcn'</code> .

The time advancement algorithm used by `play` is based on animation frames counted by ticks:

```
ticks = ticks + 1;
time = tstart + ticks*FramesPerSecond*TimeScaling;
```

where

<code>TimeScaling</code>	Specify the seconds of animation data per second of wall-clock time.
--------------------------	--

`FramesPerSecond` Specify the number of frames per second used to animate the `'TimeseriesSource'`.

For default `'TimeseriesReadFcn'` methods, the last frame played is the last time value.

Time is in seconds, position values are in the same units as the geometry model to be used by FlightGear (see the property `'GeometryModelName'`), and all angles are in radians. A possible result of using incorrect units is the early termination of the FlightGear flight simulator.

Note If there is a 15% difference between the expected time advance and the actual time advance, this method will generate the following warning:

```
TimerPeriod has been set to <value>. You may wish to modify the animation
TimeScaling and FramesPerSecond properties to compensate for the
millisecond limit of the TimerPeriod. See documentation for details.
```

The `play` method supports FlightGear animation objects with custom timers.

Limitations

The following are limitations for the `TStart` and `TFinal` values:

- `TStart` and `TFinal` must be numeric.
- `TStart` and `TFinal` cannot be `Inf` or `NaN`.
- `TFinal` must be greater than or equal to `TStart`.
- `TFinal` cannot be greater than the maximum `Timeseries` time.
- `TStart` cannot be less than the minimum `Timeseries` time.

Examples

Animate FlightGear flight simulator using the given `'Array3DoF'` position/angle time series data:

```
data = [86.2667 -2.13757034184404 7050.896596 -0.135186746141248;...
      87.2833 -2.13753906554384 6872.545051 -0.117321084678936;...
      88.2583 -2.13751089592972 6719.405713 -0.145815609299676;...
      89.275 -2.13747984652232 6550.117118 -0.150635248762596;...
      90.2667 -2.13744993157894 6385.05883 -0.143124782831999;...
      91.275 -2.13742019116849 6220.358163 -0.147946202530756;...
      92.275 -2.13739055547779 6056.906647 -0.167529704309343;...
      93.2667 -2.13736104196014 5892.356118 -0.152547361677911;...
      94.2583 -2.13733161570895 5728.201718 -0.161979312941906;...
      95.2583 -2.13730231163081 5562.923808 -0.122276929636682;...
      96.2583 -2.13727405475022 5406.736322 -0.160421658944379;...
      97.2667 -2.1372440001805 5239.138477 -0.150591353731908;...
      98.2583 -2.13721598764601 5082.78798 -0.147737722951605];
h = fganimation
h.TimeseriesSource = data
h.TimeseriesSourceType = 'Array3DoF'
play(h)
```

Animate FlightGear flight simulator using the custom timer, `MyFGTimer`.

```
h.play('MyFGTimer')
```

See Also

GenerateRunScript | initialize | update

Introduced in R2007a

play (Aero.VirtualRealityAnimation)

Animate virtual reality world for given position and angle in time series data

Syntax

```
play(h)
h.play
```

Description

`play(h)` and `h.play` animate the virtual reality world in `h` for the current `TimeseriesDataSource` at the specified rate given by the `'TimeScaling'` property (in seconds of animation data per second of wall-clock time) and animated at a certain number of frames per second using the `'FramesPerSecond'` property.

The time series data is interpreted according to the `'TimeseriesSourceType'` property, which can be one of:

<code>'timeseries'</code>	MATLAB time series data with six values per time: <code>x y z phi theta psi</code> The values are resampled.
<code>'Simulink.Timeseries'</code>	Simulink.Timeseries (Simulink signal logging): <ul style="list-style-type: none"> • First data item <code>x y z</code> • Second data item <code>phi theta psi</code>
<code>'StructureWithTime'</code>	Simulink struct with time (for example, Simulink root output logging <code>'Structure with time'</code>): <ul style="list-style-type: none"> • <code>signals(1).values: x y z</code> • <code>signals(2).values: phi theta psi</code> <p>Signals are linearly interpolated vs. time using <code>interp1</code>.</p>
<code>'Array6DoF'</code>	A double-precision array in <code>n</code> rows and 7 columns for 6-DoF data: <code>time x y z phi theta psi</code> . If a double-precision array of 8 or more columns is in <code>'TimeseriesSource'</code> , the first 7 columns are used as 6-DoF data.
<code>'Array3DoF'</code>	A double-precision array in <code>n</code> rows and 4 columns for 3-DoF data: <code>time x z theta</code> . If a double-precision array of 5 or more columns is in <code>'TimeseriesSource'</code> , the first 4 columns are used as 3-DoF data.

'Custom' Position and angle data is retrieved from 'TimeseriesSource' by the currently registered 'TimeseriesReadFcn'.

The time advancement algorithm used by play is based on animation frames counted by ticks:

```
ticks = ticks + 1;
time = tstart + ticks*FramesPerSecond*TimeScaling;
```

where

TimeScaling Specify the seconds of animation data per second of wall-clock time.
 FramesPerSecond Specify the number of frames per second used to animate the 'TimeseriesSource'.

For default 'TimeseriesReadFcn' methods, the last frame played is the last time value.

Time is in seconds, position values are in the same units as the geometry data loaded into the animation object, and all angles are in radians.

Examples

Animate virtual reality world, `asttkoff`.

```
h = Aero.VirtualRealityAnimation;
h.FramesPerSecond = 10;
h.TimeScaling = 5;
h.VRWorldFilename = [matlabroot, '/toolbox/aero/astdemos/asttkoff.wrl'];
copyfile(h.VRWorldFilename, [tempdir, 'asttkoff.wrl'], 'f');
h.VRWorldFilename = [tempdir, 'asttkoff.wrl'];
h.initialize();
load takeoffData
[~, idxPlane] = find(strcmp('Plane', h.nodeInfo));
h.Nodes{idxPlane}.TimeseriesSource = takeoffData;
h.Nodes{idxPlane}.TimeseriesSourceType = 'StructureWithTime';
h.Nodes{idxPlane}.CoordTransformFcn = @vranimCustomTransform;
h.play();
```

See Also

`initialize`

Introduced in R2007b

play

Play satellite scenario simulation results on viewer

Syntax

```
play(scenario)
play(v)
play(scenario,Name,Value)
```

Description

`play(scenario)` plays simulation results of the satellite scenario, `scenario`, from its start time (`StartTime` property) to its stop time (`StopTime` property) using a step size specified by the `SampleTime` property. The function plays the results in a satellite scenario viewer.

`play(v)` plays the satellite scenario simulation on the Satellite Scenario Viewer specified by `v`.

`play(scenario,Name,Value)` specifies additional options using one or more name-value arguments. For example, you can set the speed of animation to 40 times the real time speed, using `'PlaybackSpeedMultiplier',40`.

Examples

Add Satellites to Scenario Using Keplerian Elements

Create a satellite scenario with a start time of 02-June-2020 8:23:00 AM UTC, and the stop time set to one day later. Set the simulation sample time to 60 seconds.

```
startTime = datetime(2020,6,02,8,23,0);
stopTime = startTime + days(1);
sampleTime = 60;
sc = satelliteScenario(startTime,stopTime,sampleTime);
```

Add two satellites to the scenario using their Keplerian elements.

```
semiMajorAxis = [10000000; 15000000];
eccentricity = [0.01; 0.02];
inclination = [0; 10];
rightAscensionOfAscendingNode = [0; 15];
argumentOfPeriapsis = [0; 30];
trueAnomaly = [0; 20];

sat = satellite(sc, semiMajorAxis, eccentricity, inclination, ...
    rightAscensionOfAscendingNode, argumentOfPeriapsis, trueAnomaly)
```

```
sat =
    1×2 Satellite array with properties:
```

```
    Name
    ID
    ConicalSensors
```



```
Gimbals
Transmitters
Receivers
Accesses
GroundTrack
Orbit
OrbitPropagator
MarkerColor
MarkerSize
ShowLabel
LabelFontSize
LabelFontColor
```

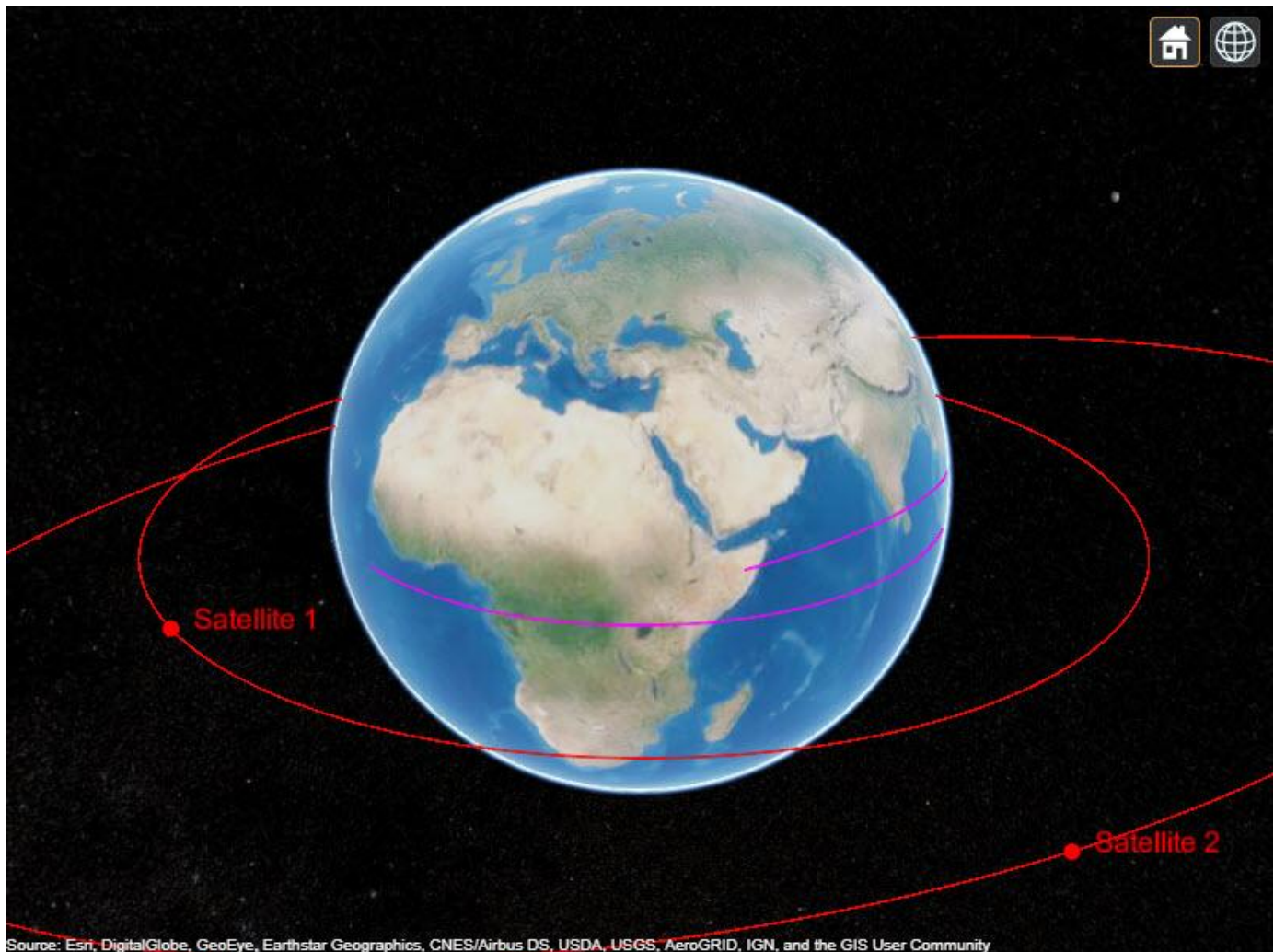
View the satellites in orbit and the ground tracks over one hour.

```
show(sat)
groundTrack(sat, 'LeadTime', 3600)

ans=1x2 object
  1x2 GroundTrack array with properties:

    LeadTime
    TrailTime
    LineWidth
    TrailLineColor
    LeadLineColor
    VisibilityMode
```

```
play(sc)
```



Input Arguments

scenario — Satellite scenario

satelliteScenario object

Satellite scenario, specified as a satelliteScenario object.

v — Viewer

scalar | vector

Viewer, specified as a scalar or vector of satelliteScenarioViewer objects.

Name-Value Pair Arguments

Specify optional comma-separated pairs of Name, Value arguments. Name is the argument name and Value is the corresponding value. Name must appear inside quotes. You can specify several name and value pair arguments in any order as Name1, Value1, . . . , NameN, ValueN.

Example: 'PlaybackSpeedMultiplier', 30 plays the animation 30 times faster than real time.

Viewer – Viewer on which to play simulation

all viewers associated with `scenario` (default) | `satelliteScenarioViewer` object

Viewer on which to play the simulation, specified as a `satelliteScenarioViewer` object.

PlaybackSpeedMultiplier – Speed of animation

50 (default) | positive scalar

Speed of animation relative to real time, specified as a positive scalar.

See Also**Objects**

`satelliteScenario`

Functions

`access` | `groundStation` | `hide` | `satellite` | `show`

Topics

“Satellite Scenario Key Concepts” on page 2-61

Introduced in R2021a

pointAt

Package: satelliteScenario

Target at which entity must be pointed

Syntax

```
pointAt(sat, coordinates)
pointAt(sat, target)
pointAt(sat, 'nadir')
```

```
pointAt(gim, 'none')
pointAt(gim, coordinates)
pointAt(gim, target)
pointAt(gim, 'nadir')
```

Description

Satellite Object

`pointAt(sat, coordinates)` sets the attitude of the satellite `sat` such that its yaw (body z axis) tracks the geographical coordinates [latitude; longitude; altitude] specified by `coordinates`. The function constantly adjusts the attitude of the satellite so that its yaw (body z) axis points at the desired target. Its roll (body x) axis is aligned with the inertial velocity vector by minimizing the angle between them (exact alignment can be geometrically impossible).

`pointAt(sat, target)` sets the attitude of the satellite `sat` such that its yaw axis tracks the specified `target`. The input `target` can be another satellite or ground station.

`pointAt(sat, 'nadir')` sets the attitude of the satellite `sat` such that its yaw axis points in the nadir direction.

Gimbal Object

`pointAt(gim, 'none')` sets the steering angles (gimbal azimuth and gimbal elevation) of the gimbal `gim` to zero.

`pointAt(gim, coordinates)` steers `gim` independent of the parent such that its body z- axis tracks the geographical coordinates [latitude; longitude; altitude] specified by `coordinates`.

The desired orientation is achieved by rotating the gimbal about its body z-axis (gimbal azimuth) and secondly rotating the gimbal about its body y-axis (gimbal elevation). The function continuously steers the gimbal for the duration of the simulation so that the gimbal points at the desired target.

`pointAt(gim, target)` steers `gim` such that its body z-axis tracks the specified `target`. `target` can be another satellite or ground station.

`pointAt(gim, 'nadir')` steers `gim` such that its body z-axis points in the nadir direction of the parent, namely, the parent's latitude, longitude, and 0 m altitude.

Input Arguments

sat — Satellite

Satellite object

Satellite, specified as a Satellite object.

gim — Gimbal

Gimbal object

Gimbal, specified as a Gimbal object.

coordinates — Geographical coordinates of the satellite target

three-element row vector

Geographical coordinates of the satellite or gimbals' target, specified as a three-element row vector. The latitude and longitude are specified in degrees, and the altitude is specified as the height above the surface of the Earth in meters.

target — Target

Satellite object | GroundStation object

Target at which input sat or gim is pointed, specified as a Satellite or GroundStation object.

See Also

Objects

satelliteScenario | satelliteScenarioViewer

Functions

access | conicalSensor | groundStation | hide | play | show

Topics

“Satellite Scenario Key Concepts” on page 2-61

Introduced in R2021a

polarMotion

Calculate Earth polar motion

Syntax

```
polarmotion=polarMotion(utc)
[polarmotion,polarmotionError]=polarMotion(utc)

polarmotion=polarMotion(utc,Name,Value)
[polarmotion,polarmotionError]=polarMotion(utc,Name,Value)
```

Description

`polarmotion=polarMotion(utc)` calculates the movement of the rotation axis with respect to the crust of the Earth for a specific Universal Coordinated Time (UTC), specified as a modified Julian date. By default, this function uses a prepopulated list of IAU 2000A Earth orientation (IERS) data. This list contains measured and calculated (predicted) data supplied by the IERS. The IERS measures and calculates this data for a set of predetermined dates.

`[polarmotion,polarmotionError]=polarMotion(utc)` calculates the error for the movement of the rotation axis with respect to the crust of the Earth.

`polarmotion=polarMotion(utc,Name,Value)` calculates the movement of the rotation axis with respect to the crust of the Earth using additional options specified by one or more `Name, Value` pair arguments.

`[polarmotion,polarmotionError]=polarMotion(utc,Name,Value)` calculates the error for the movement of the rotation axis with respect to the crust of the Earth.

Examples

Calculate Polar Motion

Calculate the polar motion for December 28, 2015.

```
mjd = m juliandate(2015,12,28)
polarmotion = polarMotion(mjd)
```

```
mjd =
    57384
```

```
polarmotion =
    1.0e-05 *
    0.0289    0.1233
```

Calculate Polar Motion and Error Using IERS Data

Calculate the polar motion and polar motion error for December 28, 2015 and January 10, 2016 using the `aeroiersdata.mat` file. Use the `mjuliandate` function to calculate the date as a modified Julian date.

```
mjd = mjuliandate([2015 12 28;2016 1 10])
[polarmotion,polarmotionErr] = polarMotion(mjd,'Source','aeroiersdata.mat')

mjd =
    57384
    57397

polarmotion =
    1.0e-05 *
    0.0289    0.1233
    0.0174    0.1304
```

Input Arguments

utc — Principal Universal Time (UT1) for UTC

M-by-1 array

Array of UTC dates, specified as an *M*-by-1 array, represented as modified Julian dates. Use the `mjuliandate` function to convert the UTC date to a modified Julian date.

Data Types: `double`

Name-Value Pair Arguments

Specify optional comma-separated pairs of `Name`, `Value` arguments. `Name` is the argument name and `Value` is the corresponding value. `Name` must appear inside quotes. You can specify several name and value pair arguments in any order as `Name1`, `Value1`, `...`, `NameN`, `ValueN`.

Example: `'Source','aeroiersdata.mat'`

Source — Custom list of Earth orientation data

`aeroiersdata.mat` (default) | MAT-file

Custom list of Earth orientation data, specified in a MAT-file.

action — Out-of-range action

Warning (default) | action

Out-of-range action, specified as a string.

Action to take in case of out-of-range or predicted value dates, specified as a string:

- `Warning` — Displays warning and indicates that the dates were out-of-range or predicted values.
- `Error` — Displays error and indicates that the dates were out-of-range or predicted values.
- `None` — Does not display warning or error.

Data Types: `string`

Output Arguments

polarmotion — Movement of the rotation axis with respect to the crust of the Earth

M-by-2 array

Movement of the rotation axis with respect to the crust of the Earth, *M*-by-2 array, in radians.

polarmotionError — Error for movement of the rotation axis with respect to the crust of the Earth

M-by-2 array

Error for movement of the rotation axis with respect to the crust of the Earth, specified as an *M*-by-2 array, in radians.

Compatibility Considerations

Updated `aeroiersdata.mat` file

Behavior changed in R2020b

The contents of the `aeroiersdata.mat` file have been updated. Correspondingly, the output of this function will have different results when using the default value ('`aeroiersdata.mat`') as the value of `Source`. The results reflect more accurate external data from the International Earth Rotation and Reference Systems Service (IERS).

See Also

`aeroReadIERSData` | `dcmeCI2ecef` | `deltaCIP` | `deltaUT1` | `eci2aer` | `eci2lla` | `lla2eci` | `mjuliandate`

Topics

"Estimate Sun Analemma Using Planetary Ephemerides and ECI to AER Transformation" on page 5-108

Introduced in R2018b

quat2angle

Convert quaternion to rotation angles

Syntax

```
[rotationAng1 rotationAng2 rotationAng3] = quat2angle(q)
[rotationAng1 rotationAng2 rotationAng3] = quat2angle(q,s)
```

Description

`[rotationAng1 rotationAng2 rotationAng3] = quat2angle(q)` calculates the set of rotation angles, `rotationAng1`, `rotationAng2`, `rotationAng3`, for a given quaternion, `q`. The rotation used in this function is a passive transformation between two coordinate systems.

`[rotationAng1 rotationAng2 rotationAng3] = quat2angle(q,s)` calculates the set of rotation angles `rotationAng1`, `rotationAng2`, `rotationAng3` for a given quaternion, `q`, and a specified rotation sequence, `s`.

Aerospace Toolbox uses quaternions that are defined using the scalar-first convention.

Examples

Determine Rotation Angles from Quaternion

Determine the rotation angles from `q = [1 0 1 0]`.

```
[yaw, pitch, roll] = quat2angle([1 0 1 0])
```

```
yaw =
     0
```

```
pitch =
    1.5708
```

```
roll =
     0
```

Determine Rotation Angles from Multiple Quaternions and Rotation Order

Determine the rotation angles from multiple quaternions.

```
q = [1 0 1 0; 1 0.5 0.3 0.1];
[pitch, roll, yaw] = quat2angle(q, 'YXZ')
```

```
pitch =
    1.5708
    0.8073
```

```
roll =
     0
```

```
    0.7702
yaw =
    0
    0.5422
```

Input Arguments

q — Quaternion

m-by-4 matrix | each element of *q* must be real number

Quaternion, specified as an *m*-by-4 matrix containing *m* quaternions. *q* has its scalar number as the first column.

Data Types: double

s — Rotation order

ZYX (default) | ZYZ | ZXY | ZXZ | YXZ | YXY | YZX | YZY | XYZ | XYX | XZY | XZX

Rotation order for three rotation angles, where Z is in the z-axis, Y is in the y-axis, and X is in the x-axis.

Data Types: double

Output Arguments

rotationAng1 — First rotation angles

m-array

First rotation angles, returned as an *m*-array, in radians.

rotationAng2 — Second rotation angles

m-array

Second rotation angles, returned as an *m*-array, in radians.

rotationAng3 — Third rotation angles

m-array

Third rotation angles, returned as an *m*-array, in radians.

Limitations

- The 'ZYX', 'ZXY', 'YXZ', 'YZX', 'XYZ', and 'XZY' implementations generate a *rotationAng2* angle that lies between ± 90 degrees, and *rotationAng1* and *rotationAng3* angles that lie between ± 180 degrees.
- The 'YZZ', 'ZXZ', 'YXY', 'YZY', 'XYX', and 'XZX' implementations generate a *rotationAng2* angle that lies between 0 and 180 degrees, and *rotationAng1* and *rotationAng3* angles that lie between ± 180 degrees.

See Also

[angle2dcm](#) | [angle2quat](#) | [dcm2angle](#) | [dcm2quat](#) | [quat2dcm](#)

Introduced in R2007b

quat2dcm

Convert quaternion to direction cosine matrix

Syntax

```
n = quat2dcm(q)
```

Description

`n = quat2dcm(q)` calculates the direction cosine matrix, `n`, for a given quaternion, `q`. Input `q` is an `m`-by-4 matrix containing `m` quaternions. `n` returns a 3-by-3-by-`m` matrix of direction cosine matrices. The direction cosine matrix performs the coordinate transformation of a vector in inertial axes to a vector in body axes. Each element of `q` must be a real number.

Aerospace Toolbox uses quaternions that are defined using the scalar-first convention.

Examples

Determine the direction cosine matrix from `q = [1 0 1 0]`:

```
dcm = quat2dcm([1 0 1 0])
```

```
dcm =
```

```

     0     0 -1.0000
     0  1.0000     0
  1.0000     0     0
```

Determine the direction cosine matrices from multiple quaternions:

```
q = [1 0 1 0; 1 0.5 0.3 0.1];
dcm = quat2dcm(q)
```

```
dcm(:,:,1) =
```

```

     0     0 -1.0000
     0  1.0000     0
  1.0000     0     0
```

```
dcm(:,:,2) =
```

```

  0.8519  0.3704 -0.3704
  0.0741  0.6148  0.7852
  0.5185 -0.6963  0.4963
```

See Also

[angle2dcm](#) | [angle2quat](#) | [dcm2angle](#) | [dcm2quat](#) | [quat2angle](#) | [quatrotate](#)

Introduced in R2006b

quat2rod

Convert quaternion to Euler-Rodrigues vector

Syntax

```
rod=quat2rod(quat)
```

Description

`rod=quat2rod(quat)` function calculates the Euler-Rodrigues vector, `rod`, for a given quaternion `quat`.

Aerospace Toolbox uses quaternions that are defined using the scalar-first convention.

Examples

Determine Euler-Rodrigues Vector from Quaternion

Determine the Euler-Rodrigues vector from the quaternion.

```
q = [-0.7071 0 0.7071 0]
r = quat2rod( q )
```

```
q =
```

```
    -0.7071         0     0.7071         0
r =
         0    -1.0000         0
```

Input Arguments

quat — Quaternion

M-by-4 array

M-by-4 array of quaternions. `quat` has its scalar number as the first column.

Data Types: `double`

Output Arguments

rod — Euler-Rodrigues vector

M-by-3 matrix

M-by-3 matrix containing *M* Euler-Rodrigues vectors.

Algorithms

An Euler-Rodrigues vector \vec{b} represents a rotation by integrating a direction cosine of a rotation axis with the tangent of half the rotation angle as follows:

$$\vec{b} = [b_x \ b_y \ b_z]$$

where:

$$b_x = \tan\left(\frac{1}{2}\theta\right)s_x,$$

$$b_y = \tan\left(\frac{1}{2}\theta\right)s_y,$$

$$b_z = \tan\left(\frac{1}{2}\theta\right)s_z$$

are the Rodrigues parameters. Vector \vec{s} represents a unit vector around which the rotation is performed. Due to the tangent, the rotation vector is indeterminate when the rotation angle equals $\pm\pi$ radians or ± 180 deg. Values can be negative or positive.

References

- [1] Dai, J.S. "Euler-Rodrigues formula variations, quaternion conjugation and intrinsic connections." *Mechanism and Machine Theory*, 92, 144-152. Elsevier, 2015.

See Also

[angle2rod](#) | [dcm2rod](#) | [rod2angle](#) | [rod2dcm](#) | [rod2quat](#)

Introduced in R2017a

quatconj

Calculate conjugate of quaternion

Syntax

```
n = quatconj(q)
```

Description

`n = quatconj(q)` calculates the conjugate, `n`, for a given quaternion, `q`. Input `q` is an `m`-by-4 matrix containing `m` quaternions. `n` returns an `m`-by-4 matrix of conjugates. Each element of `q` must be a real number.

Aerospace Toolbox uses quaternions that are defined using the scalar-first convention.

The quaternion has the form of

$$q = q_0 + \mathbf{i}q_1 + \mathbf{j}q_2 + \mathbf{k}q_3$$

The quaternion conjugate has the form of

$$q' = q_0 - \mathbf{i}q_1 - \mathbf{j}q_2 - \mathbf{k}q_3$$

Examples

Determine the conjugate of `q = [1 0 1 0]`:

```
conj = quatconj([1 0 1 0])
```

```
conj =
```

```
1     0    -1     0
```

References

[1] Stevens, Brian L., Frank L. Lewis, *Aircraft Control and Simulation*, Wiley-Interscience, 2nd Edition.

Extended Capabilities

C/C++ Code Generation

Generate C and C++ code using MATLAB® Coder™.

Usage notes and limitations:

Code generation for this function requires the Aerospace Blockset software.

See Also

quatdivide | quatinv | quatmod | quatmultiply | quaternorm | quatnormalize | quatrotate

Introduced in R2006b

quatdivide

Divide quaternion by another quaternion

Syntax

`n = quatdivide(q,r)`

Description

`n = quatdivide(q,r)` calculates the result of quaternion division, `n`, for two given quaternions, `q` and `r`. Inputs `q` and `r` can each be either an `m`-by-4 matrix containing `m` quaternions, or a single 1-by-4 quaternion. `n` returns an `m`-by-4 matrix of quaternion quotients. Each element of `q` and `r` must be a real number.

Aerospace Toolbox uses quaternions that are defined using the scalar-first convention.

The quaternions have the form of

$$q = q_0 + \mathbf{i}q_1 + \mathbf{j}q_2 + \mathbf{k}q_3$$

and

$$r = r_0 + \mathbf{i}r_1 + \mathbf{j}r_2 + \mathbf{k}r_3$$

The resulting quaternion from the division has the form of

$$t = \frac{q}{r} = t_0 + \mathbf{i}t_1 + \mathbf{j}t_2 + \mathbf{k}t_3$$

where

$$t_0 = \frac{(r_0q_0 + r_1q_1 + r_2q_2 + r_3q_3)}{r_0^2 + r_1^2 + r_2^2 + r_3^2}$$

$$t_1 = \frac{(r_0q_1 - r_1q_0 - r_2q_3 + r_3q_2)}{r_0^2 + r_1^2 + r_2^2 + r_3^2}$$

$$t_2 = \frac{(r_0q_2 + r_1q_3 - r_2q_0 - r_3q_1)}{r_0^2 + r_1^2 + r_2^2 + r_3^2}$$

$$t_3 = \frac{(r_0q_3 - r_1q_2 + r_2q_1 - r_3q_0)}{r_0^2 + r_1^2 + r_2^2 + r_3^2}$$

Examples

Determine the division of two 1-by-4 quaternions:

```
q = [1 0 1 0];
r = [1 0.5 0.5 0.75];
d = quatdivide(q, r)
```

```
d =  
    0.7273    0.1212    0.2424   -0.6061
```

Determine the division of a 2-by-4 quaternion by a 1-by-4 quaternion:

```
q = [1 0 1 0; 2 1 0.1 0.1];  
r = [1 0.5 0.5 0.75];  
d = quatdivide(q, r)
```

```
d =  
    0.7273    0.1212    0.2424   -0.6061  
    1.2727    0.0121   -0.7758   -0.4606
```

References

[1] Stevens, Brian L., Frank L. Lewis, *Aircraft Control and Simulation*, Wiley-Interscience, 2nd Edition.

Extended Capabilities

C/C++ Code Generation

Generate C and C++ code using MATLAB® Coder™.

Usage notes and limitations:

Code generation for this function requires the Aerospace Blockset software.

See Also

[quatconj](#) | [quatinv](#) | [quatmod](#) | [quatmultiply](#) | [quatnorm](#) | [quatnormalize](#) | [quatrotate](#)

Introduced in R2006b

quatexp

Exponential of quaternion

Syntax

```
qe=quatexp(q)
```

Description

`qe=quatexp(q)` calculates the exponential, `qe`, for the specified quaternion, `q`.

Aerospace Toolbox uses quaternions that are defined using the scalar-first convention.

Examples

Calculate the Exponential of Quaternion

Calculate the exponentials of quaternion matrix `[0 0 0.7854 0]`.

```
qe = quatexp([0 0 0.7854 0])
```

```
qe =  
    0.7071         0    0.7071         0
```

Input Arguments

q — Quaternions

M-by-4 matrix

Quaternions for which to calculate exponentials, specified as an *M*-by-4 matrix containing *M* quaternions.

Data Types: double

Output Arguments

qe — Exponential of quaternion

M-by-4 matrix

Exponential of quaternion.

References

- [1] Dam, Erik B., Martin Koch, Martin Lillholm. "Quaternions, Interpolation, and Animation." University of Copenhagen, København, Denmark, 1998.

See Also

quatconj | quatdivide | quatinterp | quatinv | quatlog | quatmod | quatmultiply |
quatnormalize | quatpower | quatrotate

Introduced in R2016a

quatinterp

Quaternion interpolation between two quaternions

Syntax

```
qi=quatinterp(p,q,f,method)
```

Description

`qi=quatinterp(p,q,f,method)` calculates the quaternion interpolation between two normalized quaternions `p` and `q` by interval fraction `f`.

`p` and `q` are the two extremes between which the function calculates the quaternion.

Aerospace Toolbox uses quaternions that are defined using the scalar-first convention.

Examples

Quaternion Interpolation Between Two Quaternions

Use interpolation to calculate quaternion between two quaternions `p=[1.0 0 1.0 0]` and `q=[-1.0 0 1.0 0]` using the SLERP method. This example uses the `quatnormalize` function to first-normalize the two quaternions to `pn` and `qn`.

```
pn = quatnormalize([1.0 0 1.0 0])
qn = quatnormalize([-1.0 0 1.0 0])
qi = quatinterp(pn,qn,0.5,'slerp')
```

pn =

0.7071	0	0.7071	0
--------	---	--------	---

qn =

-0.7071	0	0.7071	0
---------	---	--------	---

qi =

0	0	1	0
---	---	---	---

Input Arguments

p — First-normalized quaternion

M-by-4 matrix

First normalized quaternion for which to calculate the interpolation, specified as an *M*-by-4 matrix containing *M* quaternions. This quaternion must be a normalized quaternion.

Data Types: double

q – Quaternions*M*-by-4 matrix

Second normalized quaternion for which to calculate the interpolation, specified as an *M*-by-4 matrix containing *M* quaternions. This quaternion must be a normalized quaternion.

Data Types: double

f – Interval fraction*M*-by-1 matrix

Interval fraction by which to calculate the quaternion interpolation, specified as an *M*-by-1 matrix containing *M* fractions (scalar). *f* varies between 0 and 1. It represents the intermediate rotation of the quaternion to be calculated.

$q_i = (q_p, q_n, q_f)$, where:

- If *f* equals 0, q_i equals q_p .
- If *f* is between 0 and 1, q_i equals method.
- If *f* equals 1, q_i equals q_n .

Data Types: double

method – Quaternion interpolation method

'slerp' (default) | 'lerp' | 'nlerp'

Quaternion interpolation method to calculate the quaternion interpolation. These methods have different rotational velocities, depending on the interval fraction. For more information on interval fractions, see [1].

- slerp

Quaternion slerp. Spherical linear quaternion interpolation method. This method is most accurate, but also most computation intense.

$$Slerp(p, q, h) = p(p*q)^h \text{ with } h \in [0, 1].$$

- lerp

Quaternion lerp. Linear quaternion interpolation method. This method is the quickest, but is also least accurate. The method does not always generate normalized output.

$$LERP(p, q, h) = p(1 - h) + qh \text{ with } h \in [0, 1].$$

- nlerp

Normalized quaternion linear interpolation method.

$$\text{With } r = LERP(p, q, h), NLERP(p, q, h) = \frac{r}{|r|}.$$

Data Types: char

Output Arguments

qi — Interpolation of quaternion

M-by-4 matrix

Interpolation of quaternion.

References

- [1] Dam, Erik B., Martin Koch, Martin Lillholm. "Quaternions, Interpolation, and Animation." University of Copenhagen, København, Denmark, 1998.

See Also

quatconj | quatdivide | quatexp | quatinv | quatlog | quatmod | quatmultiply | quatnormalize | quatpower | quatrotate

Introduced in R2016a

quatinv

Calculate inverse of quaternion

Syntax

```
n = quatinv(q)
```

Description

`n = quatinv(q)` calculates the inverse, `n`, for a given quaternion, `q`.

Aerospace Toolbox uses quaternions that are defined using the scalar-first convention. For more information on quaternion forms, see “Algorithms” on page 4-561.

Examples

Determine Inverse

Determine the inverse of `q = [1 0 1 0]`:

```
qinv = quatinv([1 0 1 0])
```

```
qinv =
```

```
    0.5000         0   -0.5000         0
```

Input Arguments

q — Quaternion

m-by-4 matrix | real number

Quaternion, specified as an *m*-by-4 matrix containing *m* quaternions.

Data Types: `double`

Output Arguments

n — Inverse of quaternion

m-by-4 matrix

Inverse of quaternion, returned as an *m*-by-4 matrix.

Algorithms

The quaternion has the form of

$$q = q_0 + \mathbf{i}q_1 + \mathbf{j}q_2 + \mathbf{k}q_3.$$

The quaternion inverse has the form of

$$q^{-1} = \frac{q_0 - \mathbf{i}q_1 - \mathbf{j}q_2 - \mathbf{k}q_3}{q_0^2 + q_1^2 + q_2^2 + q_3^2}.$$

References

- [1] Stevens, Brian L., Frank L. Lewis, *Aircraft Control and Simulation*, Wiley-Interscience, 2nd Edition.

Extended Capabilities

C/C++ Code Generation

Generate C and C++ code using MATLAB® Coder™.

Usage notes and limitations:

Code generation for this function requires the Aerospace Blockset software.

See Also

`quatconj` | `quatdivide` | `quatmod` | `quatmultiply` | `quatnorm` | `quatnormalize` | `quatrotate`

Introduced in R2006b

quatlog

Natural logarithm of quaternion

Syntax

```
ql=quatlog(q)
```

Description

`ql=quatlog(q)` calculates the natural logarithm, `ql`, for a normalized quaternion, `q`.

Aerospace Toolbox uses quaternions that are defined using the scalar-first convention.

This function uses the relationships.

For $q = [\cos(\theta), \sin(\theta)v]$, with $\log(q) = [0, \theta v]$.

Examples

Calculate the Natural Logarithm of Quaternion

Calculate the natural logarithm of quaternion matrix `q=[1.0 0 1.0 0]`.

```
ql = quatlog(quatnormalize([1.0 0 1.0 0]))
```

```
ql =
```

```
    0         0    0.7854         0
```

Input Arguments

q — Quaternions

M-by-4 matrix

Quaternions for which to calculate the natural logarithm, specified as an *M*-by-4 matrix containing *M* quaternions. This quaternion must be a normalized quaternion.

Data Types: `double`

Output Arguments

ql — Natural logarithm of quaternion

M-by-4 matrix

Natural logarithm of quaternion.

References

- [1] Dam, Erik B., Martin Koch, Martin Lillholm. "Quaternions, Interpolation, and Animation." University of Copenhagen, København, Denmark, 1998.

See Also

`quatconj` | `quatdivide` | `quatexp` | `quatinterp` | `quatinv` | `quatmod` | `quatmultiply` | `quatnormalize` | `quatpower` | `quatrotate`

Introduced in R2016a

quatmod

Calculate modulus of quaternion

Syntax

```
n = quatmod(q)
```

Description

`n = quatmod(q)` calculates the modulus, `n`, for a given quaternion, `q`. Input `q` is an `m`-by-4 matrix containing `m` quaternions. `n` returns a column vector of `m` moduli. Each element of `q` must be a real number.

Aerospace Toolbox uses quaternions that are defined using the scalar-first convention.

The quaternion has the form of

$$q = q_0 + \mathbf{i}q_1 + \mathbf{j}q_2 + \mathbf{k}q_3$$

The quaternion modulus has the form of

$$|q| = \sqrt{q_0^2 + q_1^2 + q_2^2 + q_3^2}$$

Examples

Determine the modulus of `q = [1 0 0 0]`:

```
mod = quatmod([1 0 0 0])
```

```
mod =
```

```
1
```

References

[1] Stevens, Brian L., Frank L. Lewis, *Aircraft Control and Simulation*, Wiley-Interscience, 2nd Edition.

Extended Capabilities

C/C++ Code Generation

Generate C and C++ code using MATLAB® Coder™.

Usage notes and limitations:

Code generation for this function requires the Aerospace Blockset software.

See Also

quatconj | quatdivide | quatinv | quatmultiply | quatnorm | quatnormalize | quatrotate

Introduced in R2006b

quatmultiply

Calculate product of two quaternions

Syntax

```
quatprod = quatmultiply(q,r)
```

Description

`quatprod = quatmultiply(q,r)` calculates the quaternion product, `quatprod`, for two quaternions, `q` and `r`.

Aerospace Toolbox uses quaternions that are defined using the scalar-first convention.

Note Quaternion multiplication is not commutative.

Examples

Determine the Product of Two Quaternions

This example shows how to determine the product of two 1-by-4 quaternions.

```
q = [1 0 1 0];  
r = [1 0.5 0.5 0.75];  
mult = quatmultiply(q, r)  
  
mult = 1×4  
    0.5000    1.2500    1.5000    0.2500
```

Determine Product of a Quaternion with Itself

This example shows how to determine the product of a 1-by-4 quaternion with itself.

```
q = [1 0 1 0];  
mult = quatmultiply(q)  
  
mult = 1×4  
    0    0    2    0
```

Determine the Product of Two Different Quaternions

This example shows how to determine the product of 1-by-4 with two 1-by-4 quaternions.

```
q = [1 0 1 0];
r = [1 0.5 0.5 0.75; 2 1 0.1 0.1];
mult = quatmultiply(q, r)

mult = 2x4

    0.5000    1.2500    1.5000    0.2500
    1.9000    1.1000    2.1000   -0.9000
```

Input Arguments

q — First quaternion

m-by-4 matrix | 1-by-4 quaternion | real

First quaternion or set of quaternions, specified as an *m*-by-4 matrix or 1-by-4 quaternion. Each element must be real.

q must have its scalar number as the first column.

Data Types: double | single

r — Second quaternion

m-by-4 matrix | 1-by-4 quaternion | real

Second quaternion or set of quaternions, specified as an *m*-by-4 matrix or 1-by-4 quaternion. Each element must be real.

r must have its scalar number as the first column.

Data Types: double | single

Output Arguments

quatprod — Output quaternion product

m-by-4 matrix

Output quaternion product, returned as a *m*-by-4 matrix.

More About

q and r

Input quaternions q and r have the form:

$$q = q_0 + \mathbf{i}q_1 + \mathbf{j}q_2 + \mathbf{k}q_3$$

and

$$r = r_0 + \mathbf{i}r_1 + \mathbf{j}r_2 + \mathbf{k}r_3$$

quatprod

Output quaternion product `quatprod` has the form of

$$n = q \times r = n_0 + \mathbf{i}n_1 + \mathbf{j}n_2 + \mathbf{k}n_3$$

where

$$n_0 = (r_0q_0 - r_1q_1 - r_2q_2 - r_3q_3)$$

$$n_1 = (r_0q_1 + r_1q_0 - r_2q_3 + r_3q_2)$$

$$n_2 = (r_0q_2 + r_1q_3 + r_2q_0 - r_3q_1)$$

$$n_3 = (r_0q_3 - r_1q_2 + r_2q_1 + r_3q_0)$$

References

- [1] Stevens, Brian L., Frank L. Lewis. *Aircraft Control and Simulation*, 2nd Edition. Hoboken, NJ: John Wiley & Sons, 2003.

Extended Capabilities

C/C++ Code Generation

Generate C and C++ code using MATLAB® Coder™.

Usage notes and limitations:

Code generation for this function requires the Aerospace Blockset software.

See Also

`quatconj` | `quatdivide` | `quatinv` | `quatmod` | `quatnorm` | `quatnormalize` | `quatrotate`

Introduced in R2006b

quatnorm

Calculate norm of quaternion

Syntax

```
n = quatnorm(q)
```

Description

`n = quatnorm(q)` calculates the norm, `n`, for a given quaternion, `q`. Input `q` is an `m`-by-4 matrix containing `m` quaternions. `n` returns a column vector of `m` norms. Each element of `q` must be a real number.

Aerospace Toolbox uses quaternions that are defined using the scalar-first convention.

The quaternion has the form of

$$q = q_0 + \mathbf{i}q_1 + \mathbf{j}q_2 + \mathbf{k}q_3$$

The quaternion norm has the form of

$$\text{norm}(q) = q_0^2 + q_1^2 + q_2^2 + q_3^2$$

Examples

Determine the norm of `q = [1 0 0 0]`:

```
norm=quatnorm([.5 -.5 .5 0])
```

```
norm =
```

```
0.7500
```

References

[1] Stevens, Brian L., Frank L. Lewis, *Aircraft Control and Simulation*, Wiley-Interscience, 2nd Edition.

Extended Capabilities

C/C++ Code Generation

Generate C and C++ code using MATLAB® Coder™.

Usage notes and limitations:

Code generation for this function requires the Aerospace Blockset software.

See Also

`quatconj` | `quatdivide` | `quatinv` | `quatmod` | `quatmultiply` | `quatnormalize` | `quatrotate`

Introduced in R2006b

quatnormalize

Normalize quaternion

Syntax

```
n = quatnormalize(q)
```

Description

`n = quatnormalize(q)` calculates the normalized quaternion, `n`, for a given quaternion, `q`. Input `q` is an `m`-by-4 matrix containing `m` quaternions. `n` returns an `m`-by-4 matrix of normalized quaternions. Each element of `q` must be a real number.

Aerospace Toolbox uses quaternions that are defined using the scalar-first convention.

The quaternion has the form of

$$q = q_0 + \mathbf{i}q_1 + \mathbf{j}q_2 + \mathbf{k}q_3$$

The normalized quaternion has the form of

$$normal(q) = \frac{q_0 + \mathbf{i}q_1 + \mathbf{j}q_2 + \mathbf{k}q_3}{\sqrt{q_0^2 + q_1^2 + q_2^2 + q_3^2}}$$

Examples

Normalize `q = [1 0 1 0]`:

```
normal = quatnormalize([1 0 1 0])
```

```
normal =
```

```
    0.7071         0    0.7071         0
```

References

[1] Stevens, Brian L., Frank L. Lewis, *Aircraft Control and Simulation*, Wiley-Interscience, 2nd Edition.

Extended Capabilities

C/C++ Code Generation

Generate C and C++ code using MATLAB® Coder™.

Usage notes and limitations:

Code generation for this function requires the Aerospace Blockset software.

See Also

quatconj | quatdivide | quatinv | quatmod | quatmultiply | quaternorm | quatrotate

Introduced in R2006b

quatpower

Power of quaternion

Syntax

```
qp=quatpower(q,pow)
```

Description

`qp=quatpower(q,pow)` calculates q to the power of `pow` for a normalized quaternion, q .

Aerospace Toolbox uses quaternions that are defined using the scalar-first convention.

$q^t = \exp(t \cdot \log(q))$, with $t \in R$.

Examples

Calculate the Power of Quaternion

Calculate the power of 2 of quaternion $q = [1.0 \ 0 \ 1.0 \ 0]$.

```
qp = quatpower(quatnormalize([1.0 0 1.0 0]),2)
```

```
qp =
```

```
    -0.0000         0    1.0000         0
```

Input Arguments

q — Quaternions

M-by-4 matrix

Quaternions for which to calculate exponentials, specified as an *M*-by-4 matrix containing *M* quaternions.

Data Types: double

pow — Power

M-by-1 vector

Power to which to calculate quaternion power, specified as an *M*-by-1 vector containing *M* power scalars.

Data Types: double

Output Arguments

qp — Power of quaternion

M-by-4 matrix

Power of quaternion.

References

- [1] Dam, Erik B., Martin Koch, Martin Lillholm. "Quaternions, Interpolation, and Animation."
University of Copenhagen, København, Denmark, 1998.

See Also

`quatconj` | `quatdivide` | `quatexp` | `quatinterp` | `quatinv` | `quatlog` | `quatmod` |
`quatmultiply` | `quatnormalize` | `quatrotate`

Introduced in R2016a

quatrotate

Rotate vector by quaternion

Syntax

```
n = quatrotate(q,r)
```

Description

`n = quatrotate(q,r)` calculates the rotated vector, `n`, for a quaternion, `q`, and a vector, `r`. If quaternions are not yet normalized, the function normalizes them.

Aerospace Toolbox uses quaternions that are defined using the scalar-first convention.

Examples

Rotate a 1-by-3 Vector

This example shows how to rotate a 1-by-3 vector by a 1-by-4 quaternion.

```
q = [1 0 1 0];  
r = [1 1 1];  
n = quatrotate(q, r)  
  
n = 1×3  
    -1.0000    1.0000    1.0000
```

Rotate Two 1-by-3 Vectors by a 1-by-4 Quaternion

This example shows how to rotate two 1-by-3 vectors by a 1-by-4 quaternion.

```
q = [1 0 1 0];  
r = [1 1 1; 2 3 4];  
n = quatrotate(q, r)  
  
n = 2×3  
    -1.0000    1.0000    1.0000  
    -4.0000    3.0000    2.0000
```

Rotate a 1-by-3 Vector by Two 1-by-4 Quaternions

This example shows how to rotate a 1-by-3 vector by two 1-by-4 quaternions.


```

q = [1 0 1 0; 1 0.5 0.3 0.1];
r = [1 1 1];
n = quatrotate(q, r)

n = 2×3

    -1.0000    1.0000    1.0000
     0.8519    1.4741    0.3185

```

Rotate Multiple Vectors by Multiple Quaternions

This example shows how to rotate multiple vectors by multiple quaternions.

```

q = [1 0 1 0; 1 0.5 0.3 0.1];
r = [1 1 1; 2 3 4];
n = quatrotate(q, r)

n = 2×3

    -1.0000    1.0000    1.0000
     1.3333    5.1333    0.9333

```

Input Arguments

q — Quaternion

m-by-4 matrix | 1-by-4 array

Quaternion or set of quaternions, specified as an *m*-by-4 matrix containing *m* quaternions, or a single 1-by-4 quaternion. Each element must be real.

q must have its scalar number as the first column.

Data Types: double | single

r — Vector

m-by-3 matrix | 1-by-3 array

Vector or set of vectors to be rotated, specified as an *m*-by-3 matrix, containing *m* vectors, or a single 1-by-3 array. Each element must be real.

Data Types: double | single

Output Arguments

n — Rotated vector

m-by-3 matrix

Rotated vector, returned as an *m*-by-3 matrix.

More About

q

Quaternion q has the form:

$$q = q_0 + \mathbf{i}q_1 + \mathbf{j}q_2 + \mathbf{k}q_3$$

r

Vector r has the form:

$$v = \mathbf{i}v_1 + \mathbf{j}v_2 + \mathbf{k}v_3$$

n

Rotated vector n has the form:

$$v' = \begin{bmatrix} v_1' \\ v_2' \\ v_3' \end{bmatrix} = \begin{bmatrix} (1 - 2q_2^2 - 2q_3^2) & 2(q_1q_2 + q_0q_3) & 2(q_1q_3 - q_0q_2) \\ 2(q_1q_2 - q_0q_3) & (1 - 2q_1^2 - 2q_3^2) & 2(q_2q_3 + q_0q_1) \\ 2(q_1q_3 + q_0q_2) & 2(q_2q_3 - q_0q_1) & (1 - 2q_1^2 - 2q_2^2) \end{bmatrix} \begin{bmatrix} v_1 \\ v_2 \\ v_3 \end{bmatrix}$$

The direction cosine matrix for this equation expects a normalized quaternion.

References

- [1] Stevens, Brian L., Frank L. Lewis. *Aircraft Control and Simulation*, 2nd Edition. Hoboken, NJ: John Wiley & Sons, 2003.
- [2] Diebel, James. "Representing Attitude: Euler Angles, Unit Quaternions, and Rotation Vectors." Stanford University, Stanford, California, 2006.

See Also

quatconj | quatinv | quatmod | quatmultiply | quaternorm | quatnormalize

Introduced in R2006b

read (Aero.Geometry)

Read geometry data using current reader

Syntax

```
read(h, source)
```

Description

read(h, source) reads the geometry data of the geometry object h. source can be:

- 'Auto'
Selects default reader.
- 'Variable'
Selects MATLAB variable of type structure structures that contains the fieldsname, faces, vertices, and cdata that define the geometry in the Handle Graphics patches.
- 'MatFile'
Selects MAT-file reader.
- 'Ac3dFile'
Selects Ac3d file reader.
- 'Custom'
Selects a custom reader.

Examples

Read geometry data from Ac3d file, pa24-250_orange.ac.

```
g = Aero.Geometry;  
g.Source = 'Ac3d';  
g.read('pa24-250_orange.ac');
```

Introduced in R2007a

removeBody

Class: Aero.Animation

Package: Aero

Remove one body from animation

Syntax

```
h = removeBody(h,idx)
h = h.removeBody(idx)
```

Description

`h = removeBody(h,idx)` and `h = h.removeBody(idx)` remove the body specified by the index `idx` from the animation object `h`.

Input Arguments

<code>h</code>	Animation object.
<code>idx</code>	Body specified with this index.

Examples

Remove the body identified by the index, 1.

```
h = Aero.Animation;
idx1 = h.createBody('pa24-250_orange.ac', 'Ac3d');
h = removeBody(h,1)
```

removeNode (Aero.VirtualRealityAnimation)

Remove node from virtual reality animation object

Syntax

```
removeNode(h,node)  
h.removeNode(node)
```

Description

`removeNode(h,node)` and `h.removeNode(node)` remove the node specified by `node` from the virtual reality animation object `h`. `node` can be either the node name or the node index. This function can remove only one node at a time.

Note You can use only this function to remove a node added by `addNode`. If you need to remove a node from a previously defined `.wrl` file, use a VRML editor.

Examples

Remove the node, Lynx1.

```
h = Aero.VirtualRealityAnimation;  
h.VRWorldFilename = [matlabroot,'/toolbox/aero/astdemos/asttkoff.wrl'];  
copyfile(h.VRWorldFilename,[tempdir,'asttkoff.wrl'],'f');  
h.VRWorldFilename = [tempdir,'asttkoff.wrl'];  
h.initialize();  
h.addNode('Lynx1',[matlabroot,'/toolbox/aero/astdemos/chaseHelicopter.wrl']);  
h.removeNode('Lynx1');
```

See Also

`addNode`

Introduced in R2007b

removeViewpoint (Aero.VirtualRealityAnimation)

Remove viewpoint node from virtual reality animation

Syntax

```
removeViewpoint(h,viewpoint)
h.removeViewpoint(viewpoint)
```

Description

`removeViewpoint(h,viewpoint)` and `h.removeViewpoint(viewpoint)` remove the viewpoint specified by `viewpoint` from the virtual reality animation object `h`. `viewpoint` can be either the viewpoint name or the viewpoint index. This function can remove only one viewpoint at a time.

Note You can use this function to remove a viewpoint added by `addViewpoint`. If you need to remove a viewpoint from a previously defined `.wrl` file, use a VRML editor.

Examples

Remove the node, Lynx1.

```
h = Aero.VirtualRealityAnimation;
h.VRWorldFilename = [matlabroot,'/toolbox/aero/astdemos/asttkoff.wrl'];
copyfile(h.VRWorldFilename,[tempdir,'asttkoff.wrl'],'f');
h.VRWorldFilename = [tempdir,'asttkoff.wrl'];
h.initialize();
h.addViewpoint(h.Nodes{2}.VRNode,'children','chaseView','View From Helicopter');
h.removeViewpoint('chaseView');
```

See Also

`addViewpoint`

Introduced in R2007b

rod2angle

Convert Euler-Rodrigues vector to rotation angles

Syntax

```
[R1 R2 R3]=rod2angle(rod)
[R1 R2 R3]=rod2angle(rod,S)
```

Description

`[R1 R2 R3]=rod2angle(rod)` function calculates the set of rotation angles, R1, R2, and R3, for a given Euler-Rodrigues (also known as Rodrigues) vector, `rod`. The rotation used in this function is a passive transformation between two coordinate systems.

`[R1 R2 R3]=rod2angle(rod,S)` function calculates the set of rotation angles for a given Rodrigues vector and a specified rotation sequence, `S`.

Examples

Determine Rotation Angles from One Vector

Determine rotation angles from vector, `[.1 .2 -.1]`.

```
r = [.1 .2 -.1];
[yaw, pitch, roll] = rod2angle(r)
```

```
yaw =
    -0.1651
```

```
pitch =
    0.4074
```

```
roll =
    0.1651
```

Input Arguments

rod — Rodrigues vector

M-by-3 matrix

M-by-3 matrix containing *M* Rodrigues vector.

Data Types: double

S — Rotation sequence

ZYX (default) | ZYZ | ZXY | ZXZ | YXZ | YXY | YZX | YZY | XYZ | YXY | XZY | XZX

Rotation angles, in radians, from which to determine Rodrigues vector. For the default rotation sequence, ZYX, the rotation angle order is:

- R1 — z-axis rotation
- R2 — y-axis rotation
- R3 — x-axis rotation

Data Types: char | string

Output Arguments

R1 — First rotation angles

M-by-1 array

M-by-1 array of first rotation angles, in radians.

R2 — Second rotation angles

M-by-1 array

M-by-1 array of second rotation angles, in radians.

R3 — Third rotation angles

M-by-1 array

M-by-1 array of third rotation angles, in radians.

Algorithms

An Euler-Rodrigues vector \vec{b} represents a rotation by integrating a direction cosine of a rotation axis with the tangent of half the rotation angle as follows:

$$\vec{b} = [b_x \ b_y \ b_z]$$

where:

$$b_x = \tan\left(\frac{1}{2}\theta\right)s_x,$$

$$b_y = \tan\left(\frac{1}{2}\theta\right)s_y,$$

$$b_z = \tan\left(\frac{1}{2}\theta\right)s_z$$

are the Rodrigues parameters. Vector \vec{s} represents a unit vector around which the rotation is performed. Due to the tangent, the rotation vector is indeterminate when the rotation angle equals $\pm\pi$ radians or ± 180 deg. Values can be negative or positive.

References

- [1] Dai, J.S. "Euler-Rodrigues formula variations, quaternion conjugation and intrinsic connections." *Mechanism and Machine Theory*, 92, 144-152. Elsevier, 2015.

See Also

[angle2rod](#) | [dcm2rod](#) | [quat2rod](#) | [rod2dcm](#) | [rod2quat](#)

Introduced in R2017a

rod2dcm

Convert Euler-Rodrigues vector to direction cosine matrix

Syntax

```
dcm=rod2dcm(R)
```

Description

`dcm=rod2dcm(R)` function calculates the direction cosine matrix, for a given Euler-Rodrigues (also known as Rodrigues) vector, R .

Examples

Determine Direction Cosine Matrix from Euler-Rodrigues Vector

Determine the direction cosine matrix from the Euler-Rodrigues vector.

```
r = [.1 .2 -.1];  
DCM = rod2dcm(r)
```

DCM =

```
    0.9057    -0.1509    -0.3962  
    0.2264     0.9623     0.1509  
    0.3585    -0.2264     0.9057
```

Input Arguments

R — Rodrigues vector

M -by-3 matrix

M -by-3 matrix containing M Rodrigues vectors.

Data Types: `double`

Output Arguments

dcm — Direction cosine matrix

3-by-3-by- M matrix

3-by-3-by- M containing M direction cosine matrices.

Algorithms

An Euler-Rodrigues vector \vec{b} represents a rotation by integrating a direction cosine of a rotation axis with the tangent of half the rotation angle as follows:

$$\vec{b} = [b_x \ b_y \ b_z]$$

where:

$$b_x = \tan\left(\frac{1}{2}\theta\right)s_x,$$

$$b_y = \tan\left(\frac{1}{2}\theta\right)s_y,$$

$$b_z = \tan\left(\frac{1}{2}\theta\right)s_z$$

are the Rodrigues parameters. Vector \vec{s} represents a unit vector around which the rotation is performed. Due to the tangent, the rotation vector is indeterminate when the rotation angle equals $\pm\pi$ radians or ± 180 deg. Values can be negative or positive.

References

- [1] Dai, J.S. "Euler-Rodrigues formula variations, quaternion conjugation and intrinsic connections." *Mechanism and Machine Theory*, 92, 144-152. Elsevier, 2015.

See Also

[angle2rod](#) | [dcm2rod](#) | [quat2rod](#) | [rod2angle](#) | [rod2quat](#)

Introduced in R2017a

rod2quat

Convert Euler-Rodrigues vector to quaternion

Syntax

```
quat=rod2quat(R)
```

Description

`quat=rod2quat(R)` function calculates the quaternion, `quat`, for a given Euler-Rodrigues (also known as Rodrigues) vector, `R`.

Aerospace Toolbox uses quaternions that are defined using the scalar-first convention.

Examples

Determine Quaternion from Rodrigues Vector

Determine the quaternion from Rodrigues vector.

```
r = [.1 .2 -.1];  
q = rod2quat(r)
```

```
q =
```

```
    0.9713    0.0971    0.1943   -0.0971
```

Input Arguments

R — Rodrigues vector

M-by-1 matrix

M-by-1 array of Rodrigues vectors.

Data Types: `double`

Output Arguments

quat — Rodrigues vector

M-by-4 matrix

M-by-4 matrix of *M* quaternions. `quat` has its scalar number as the first column.

Algorithms

An Euler-Rodrigues vector \vec{b} represents a rotation by integrating a direction cosine of a rotation axis with the tangent of half the rotation angle as follows:

$$\vec{b} = [b_x \ b_y \ b_z]$$

where:

$$b_x = \tan\left(\frac{1}{2}\theta\right)s_x,$$

$$b_y = \tan\left(\frac{1}{2}\theta\right)s_y,$$

$$b_z = \tan\left(\frac{1}{2}\theta\right)s_z$$

are the Rodrigues parameters. Vector \vec{s} represents a unit vector around which the rotation is performed. Due to the tangent, the rotation vector is indeterminate when the rotation angle equals $\pm\pi$ radians or ± 180 deg. Values can be negative or positive.

References

- [1] Dai, J.S. "Euler-Rodrigues formula variations, quaternion conjugation and intrinsic connections." *Mechanism and Machine Theory*, 92, 144-152. Elsevier, 2015.

See Also

[angle2rod](#) | [dcm2rod](#) | [quat2rod](#) | [rod2angle](#) | [rod2dcm](#)

Introduced in R2017a

RPMIndicator Properties

Control revolutions per minute (RPM) indicator appearance and behavior

Description

RPM indicators are components that represent an RPM indicator. Properties control the appearance and behavior of an RMP indicator. Use dot notation to refer to a particular object and property:

```
f = uifigure;
rpm = uiaerorpm(f);
rpm.Value = 100;
```

The RPM indicator displays measurements for engine revolutions per minute in percentage of RPM.

The range of values for RPM goes from 0 to 110%. Minor ticks represent increments of 5% RPM and major ticks represent increments of 10% RPM.

Properties

RMP Indicator

Limits — Minimum and maximum indicator scale values

two-element finite, real, and scalar numeric array | read-only

Minimum and maximum indicator scale values, specified as a two-element numeric array. This value is read-only.

RPM — Location of RPM indicator needle

0 (default) | finite, real, and scalar numeric

Location of the RPM indicator needle, specified a finite and scalar numeric rev/min.

- Changing the value changes the location of the to align with the corresponding value on the indicator.

Example: 60

Dependencies

Specifying this value changes the value of `Value`.

Data Types: `double`

ScaleColors — Scale colors

[] (default) | 1-by-n string array | 1-by-n cell array | n-by-3 array of RGB triplets | hexadecimal color code | ...

Scale colors, specified as one of the following arrays:





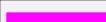



- A 1-by-n string array of color options, such as ["blue" "green" "red"].
- An n-by-3 array of RGB triplets, such as [0 0 1;1 1 0].

- A 1-by-n cell array containing RGB triplets, hexadecimal color codes, or named color options. For example, {'#EDB120', '#7E2F8E', '#77AC30'}.








RGB triplets and hexadecimal color codes are useful for specifying custom colors.

- An RGB triplet is a three-element row vector whose elements specify the intensities of the red, green, and blue components of the color. The intensities must be in the range [0, 1]; for example, [0.4 0.6 0.7].
- A hexadecimal color code is a character vector or a string scalar that starts with a hash symbol (#) followed by three or six hexadecimal digits, which can range from 0 to F. The values are not case sensitive. Thus, the color codes '#FF8800', '#ff8800', '#F80', and '#f80' are equivalent.

Alternatively, you can specify some common colors by name. This table lists the named color options, the equivalent RGB triplets, and hexadecimal color codes.

Color Name	Short Name	RGB Triplet	Hexadecimal Color Code	Appearance
'red'	'r'	[1 0 0]	'#FF0000'	
'green'	'g'	[0 1 0]	'#00FF00'	
'blue'	'b'	[0 0 1]	'#0000FF'	
'cyan'	'c'	[0 1 1]	'#00FFFF'	
'magenta'	'm'	[1 0 1]	'#FF00FF'	
'yellow'	'y'	[1 1 0]	'#FFFF00'	
'black'	'k'	[0 0 0]	'#000000'	
'white'	'w'	[1 1 1]	'#FFFFFF'	

Here are the RGB triplets and hexadecimal color codes for the default colors MATLAB uses in many types of plots.

RGB Triplet	Hexadecimal Color Code	Appearance
[0 0.4470 0.7410]	'#0072BD'	
[0.8500 0.3250 0.0980]	'#D95319'	
[0.9290 0.6940 0.1250]	'#EDB120'	
[0.4940 0.1840 0.5560]	'#7E2F8E'	
[0.4660 0.6740 0.1880]	'#77AC30'	
[0.3010 0.7450 0.9330]	'#4DBEEE'	
[0.6350 0.0780 0.1840]	'#A2142F'	

Each color of the ScaleColors array corresponds to a colored section of the gauge. Set the ScaleColorLimits property to map the colors to specific sections of the gauge.

If you do not set the ScaleColorLimits property, MATLAB distributes the colors equally over the range of the gauge.

ScaleColorLimits — Scale color limits

[] (default) | n-by-2 array

Scale color limits, specified as an n-by-2 array of numeric values. For every row in the array, the first element must be less than the second element.

When applying colors to the gauge, MATLAB applies the colors starting with the first color in the `ScaleColors` array. Therefore, if two rows in `ScaleColorLimits` array overlap, then the color applied later takes precedence.

The gauge does not display any portion of the `ScaleColorLimits` that falls outside of the `Limits` property.

If the `ScaleColors` and `ScaleColorLimits` property values are different sizes, then the gauge shows only the colors that have matching limits. For example, if the `ScaleColors` array has three colors, but the `ScaleColorLimits` has only two rows, then the gauge displays the first two color/limit pairs only.

Value — Location of RPM indicator needle

0 (default) | finite, real, and scalar numeric

Location of the RPM indicator needle, specified a finite and scalar numeric rev/min.

- Changing the value changes the location of the to align with the corresponding value on the indicator.

Example: 60

Dependencies

Specifying this value changes the value of RPM.

Data Types: `double`

Interactivity

Visible — Visibility of RPM indicator

'on' (default) | on/off logical value

Visibility of the RPM indicator, specified as 'on' or 'off', or as numeric or logical 1 (true) or 0 (false). A value of 'on' is equivalent to true, and 'off' is equivalent to false. Thus, you can use the value of this property as a logical value. The value is stored as an on/off logical value of type `matlab.lang.OnOffSwitchState`. The `Visible` property determines whether the RPM indicator is displayed on the screen. If the `Visible` property is set to 'off', then the entire RPM indicator is hidden, but you can still specify and access its properties.

ContextMenu — Context menu

empty `GraphicsPlaceholder` array (default) | `ContextMenu` object

Context menu, specified as a `ContextMenu` object created using the `uicontextmenu` function. Use this property to display a context menu when you right-click on a component.

Enable — Operational state of RPM indicator

'on' (default) | on/off logical value

Operational state of RPM indicator, specified as 'on' or 'off', or as numeric or logical 1 (true) or 0 (false). A value of 'on' is equivalent to true, and 'off' is equivalent to false. Thus, you can use the value of this property as a logical value. The value is stored as an on/off logical value of type `matlab.lang.OnOffSwitchState`.

- If you set this property to 'on', then the appearance of the RPM indicator indicates that the RPM indicator is operational.
- If you set this property to 'off', then the appearance of the RPM indicator appears dimmed, indicating that the RPM indicator is not operational.

Position

Position — Location and size of RPM indicator

[100 100 120 120] (default) | [left bottom width height]

Location and size of the RPM indicator relative to the parent container, specified as the vector, [left bottom width height]. This table describes each element in the vector.

Element	Description
left	Distance from the inner left edge of the parent container to the outer left edge of an imaginary box surrounding the RPM indicator
bottom	Distance from the inner bottom edge of the parent container to the outer bottom edge of an imaginary box surrounding the RPM indicator
width	Distance between the right and left outer edges of the RPM indicator
height	Distance between the top and bottom outer edges of the RPM indicator

All measurements are in pixel units.

The **Position** values are relative to the drawable area of the parent container. The drawable area is the area inside the borders of the container and does not include the area occupied by decorations such as a menu bar or title.

Example: [200 120 120 120]

InnerPosition — Inner location and size of RPM indicator

[100 100 120 120] (default) | [left bottom width height]

Inner location and size of the RPM indicator, specified as [left bottom width height]. Position values are relative to the parent container. All measurements are in pixel units. This property value is identical to the **Position** property.

OuterPosition — Outer location and size of RPM indicator

[100 100 120 120] (default) | [left bottom width height]

This property is read-only.

Outer location and size of the RPM indicator returned as [left bottom width height]. Position values are relative to the parent container. All measurements are in pixel units. This property value is identical to the **Position** property.

Layout — Layout options

empty `LayoutOptions` array (default) | `GridLayoutOptions` object

Layout options, specified as a `GridLayoutOptions` object. This property specifies options for components that are children of grid layout containers. If the component is not a child of a grid layout

container (for example, it is a child of a figure or panel), then this property is empty and has no effect. However, if the component is a child of a grid layout container, you can place the component in the desired row and column of the grid by setting the `Row` and `Column` properties on the `GridLayoutOptions` object.

For example, this code places an RPM indicator in the third row and second column of its parent grid.

```
g = uigridlayout([4 3]);  
gauge = uiaerorpm(g);  
gauge.Layout.Row = 3;  
gauge.Layout.Column = 2;
```

To make the RPM indicator span multiple rows or columns, specify the `Row` or `Column` property as a two-element vector. For example, this RPM indicator spans columns 2 through 3:

```
gauge.Layout.Column = [2 3];
```

Callbacks

CreateFcn — Creation function

' ' (default) | function handle | cell array | character vector

Object creation function, specified as one of these values:

- Function handle.
- Cell array in which the first element is a function handle. Subsequent elements in the cell array are the arguments to pass to the callback function.
- Character vector containing a valid MATLAB expression (not recommended). MATLAB evaluates this expression in the base workspace.

For more information about specifying a callback as a function handle, cell array, or character vector, see “Write Callbacks in App Designer”.

This property specifies a callback function to execute when MATLAB creates the object. MATLAB initializes all property values before executing the `CreateFcn` callback. If you do not specify the `CreateFcn` property, then MATLAB executes a default creation function.

Setting the `CreateFcn` property on an existing component has no effect.

If you specify this property as a function handle or cell array, you can access the object that is being created using the first argument of the callback function. Otherwise, use the `gcbo` function to access the object.

DeleteFcn — Deletion function

' ' (default) | function handle | cell array | character vector

Object deletion function, specified as one of these values:

- Function handle.
- Cell array in which the first element is a function handle. Subsequent elements in the cell array are the arguments to pass to the callback function.
- Character vector containing a valid MATLAB expression (not recommended). MATLAB evaluates this expression in the base workspace.

For more information about specifying a callback as a function handle, cell array, or character vector, see “Write Callbacks in App Designer”.

This property specifies a callback function to execute when MATLAB deletes the object. MATLAB executes the `DeleteFcn` callback before destroying the properties of the object. If you do not specify the `DeleteFcn` property, then MATLAB executes a default deletion function.

If you specify this property as a function handle or cell array, you can access the object that is being deleted using the first argument of the callback function. Otherwise, use the `gcbo` function to access the object.

Callback Execution Control

Interruptible — Callback interruption

'on' (default) | on/off logical value

Callback interruption, specified as 'on' or 'off', or as numeric or logical 1 (true) or 0 (false). A value of 'on' is equivalent to true, and 'off' is equivalent to false. Thus, you can use the value of this property as a logical value. The value is stored as an on/off logical value of type `matlab.lang.OnOffSwitchState`.

This property determines if a running callback can be interrupted. There are two callback states to consider:

- The running callback is the currently executing callback.
- The interrupting callback is a callback that tries to interrupt the running callback.

Whenever MATLAB invokes a callback, that callback attempts to interrupt the running callback (if one exists). The `Interruptible` property of the object owning the running callback determines if interruption is allowed.

- A value of 'on' allows other callbacks to interrupt the object's callbacks. The interruption occurs at the next point where MATLAB processes the queue, such as when there is a `drawnow`, `figure`, `uifigure`, `getframe`, `waitfor`, or `pause` command.
 - If the running callback contains one of those commands, then MATLAB stops the execution of the callback at that point and executes the interrupting callback. MATLAB resumes executing the running callback when the interrupting callback completes.
 - If the running callback does not contain one of those commands, then MATLAB finishes executing the callback without interruption.
- A value of 'off' blocks all interruption attempts. The `BusyAction` property of the object owning the interrupting callback determines if the interrupting callback is discarded or put into a queue.

Note Callback interruption and execution behave differently in these situations:

- If the interrupting callback is a `DeleteFcn`, `CloseRequestFcn` or `SizeChangedFcn` callback, then the interruption occurs regardless of the `Interruptible` property value.
- If the running callback is currently executing the `waitfor` function, then the interruption occurs regardless of the `Interruptible` property value.
- Timer objects execute according to schedule regardless of the `Interruptible` property value.

When an interruption occurs, MATLAB does not save the state of properties or the display. For example, the object returned by the `gca` or `gcf` command might change when another callback executes.

BusyAction — Callback queuing

'queue' (default) | 'cancel'

Callback queuing, specified as 'queue' or 'cancel'. The `BusyAction` property determines how MATLAB handles the execution of interrupting callbacks. There are two callback states to consider:

- The running callback is the currently executing callback.
- The interrupting callback is a callback that tries to interrupt the running callback.

Whenever MATLAB invokes a callback, that callback attempts to interrupt a running callback. The `Interruptible` property of the object owning the running callback determines if interruption is permitted. If interruption is not permitted, then the `BusyAction` property of the object owning the interrupting callback determines if it is discarded or put in the queue. These are possible values of the `BusyAction` property:

- 'queue' — Puts the interrupting callback in a queue to be processed after the running callback finishes execution.
- 'cancel' — Does not execute the interrupting callback.

BeingDeleted — Deletion status

on/off logical value

This property is read-only.

Deletion status, returned as an on/off logical value of type `matlab.lang.OnOffSwitchState`.

MATLAB sets the `BeingDeleted` property to 'on' when the `DeleteFcn` callback begins execution. The `BeingDeleted` property remains set to 'on' until the component object no longer exists.

Check the value of the `BeingDeleted` property to verify that the object is not about to be deleted before querying or modifying it.

Parent/Child

HandleVisibility — Visibility of object handle

'on' (default) | 'callback' | 'off'

Visibility of the object handle, specified as 'on', 'callback', or 'off'.

This property controls the visibility of the object in its parent's list of children. When an object is not visible in its parent's list of children, it is not returned by functions that obtain objects by searching the object hierarchy or querying properties. These functions include `get`, `findobj`, `clf`, and `close`. Objects are valid even if they are not visible. If you can access an object, you can set and get its properties, and pass it to any function that operates on objects.

HandleVisibility Value	Description
'on'	The object is always visible.

HandleVisibility Value	Description
'callback'	The object is visible from within callbacks or functions invoked by callbacks, but not from within functions invoked from the command line. This option blocks access to the object at the command-line, but allows callback functions to access it.
'off'	The object is invisible at all times. This option is useful for preventing unintended changes to the UI by another function. Set the HandleVisibility to 'off' to temporarily hide the object during the execution of that function.

Parent — Parent container

Figure object (default) | Panel object | Tab object | ButtonGroup object | GridLayout object

Parent container, specified as a Figure object created using the `uifigure` function, or one of its child containers: `Tab`, `Panel`, `ButtonGroup`, or `GridLayout`. If no container is specified, MATLAB calls the `uifigure` function to create a new Figure object that serves as the parent container.

Identifiers**Type — Type of graphics object**

'uiaerorpm'

This property is read-only.

Type of graphics object, returned as 'uiaerorpm'.

Tag — Object identifier

' ' (default) | character vector | string scalar

Object identifier, specified as a character vector or string scalar. You can specify a unique Tag value to serve as an identifier for an object. When you need access to the object elsewhere in your code, you can use the `findobj` function to search for the object based on the Tag value.

UserData — User data

[] (default) | array

User data, specified as any MATLAB array. For example, you can specify a scalar, vector, matrix, cell array, character array, table, or structure. Use this property to store arbitrary data on an object.

If you are working in App Designer, create public or private properties in the app to share data instead of using the `UserData` property. For more information, see “Share Data Within App Designer Apps”.

See Also

uiaerorpm

Topics

“Create and Configure Flight Instrument Component and an Animation Object” on page 2-49

“Display Flight Trajectory Data Using Flight Instruments and Flight Animation” on page 5-111

Introduced in R2018b

rrdelta

Compute relative pressure ratio

Syntax

```
d = rrdelta(p0, mach, g)
```

Description

`d = rrdelta(p0, mach, g)` computes `m` pressure relative ratios, `d`, from `m` static pressures, `p0`, `m` Mach numbers, `mach`, and `m` specific heat ratios, `g`. `p0` must be in pascals.

Examples

Determine the relative pressure ratio for three pressures:

```
delta = rrdelta([101325 22632.0672 4328.1393], 0.5, 1.4)
```

```
delta =
```

```
    1.1862    0.2650    0.0507
```

Determine the relative pressure ratio for three pressures and three different heat ratios:

```
delta = rrdelta([101325 22632.0672 4328.1393], 0.5, [1.4 1.35 1.4])
```

```
delta =
```

```
    1.1862    0.2635    0.0507
```

Determine the relative pressure ratio for three pressures at three different conditions:

```
delta = rrdelta([101325 22632.0672 4328.1393], [0.5 1 2], [1.4 1.35 1.4])
```

```
delta =
```

```
    1.1862    0.4161    0.3342
```

Assumptions and Limitations

For cases in which total pressure ratio is desired (Mach number is nonzero), the total pressures are calculated assuming perfect gas (with constant molecular weight, constant pressure specific heat, and constant specific heat ratio) and dry air.

References

Aeronautical Vestpocket Handbook, United Technologies Pratt & Whitney, August, 1986

See Also

`rrsigma` | `rrtheta`

Introduced in R2006b

rrsigma

Compute relative density ratio

Syntax

```
s = rrsigma(rho, mach, g)
```

Description

`s = rrsigma(rho, mach, g)` computes m density relative ratios, s , from m static densities, ρ , m Mach numbers, mach , and m specific heat ratios, g . ρ must be in kilograms per meter cubed.

Examples

Determine the relative density ratio for three densities:

```
sigma = rrsigma([1.225 0.3639 0.0953], 0.5, 1.4)
```

```
sigma =
```

```
1.1297    0.3356    0.0879
```

Determine the relative density ratio for three densities and three different heat ratios:

```
sigma = rrsigma([1.225 0.3639 0.0953], 0.5, [1.4 1.35 1.4])
```

```
sigma =
```

```
1.1297    0.3357    0.0879
```

Determine the relative density ratio for three densities at three different conditions:

```
sigma = rrsigma([1.225 0.3639 0.0953], [0.5 1 2], [1.4 1.35 1.4])
```

```
sigma =
```

```
1.1297    0.4709    0.3382
```

Assumptions and Limitations

For cases in which total density ratio is desired (Mach number is nonzero), the total density is calculated assuming perfect gas (with constant molecular weight, constant pressure specific heat, and constant specific heat ratio) and dry air.

References

Aeronautical Vestpocket Handbook, United Technologies Pratt & Whitney, August, 1986

See Also

rrdelta | rrtheta

Introduced in R2006b

rrtheta

Compute relative temperature ratio

Syntax

```
th = rrtheta(t0, mach, g)
```

Description

`th = rrtheta(t0, mach, g)` computes *m* temperature relative ratios, *th*, from *m* static temperatures, *t0*, *m* Mach numbers, *mach*, and *m* specific heat ratios, *g*. *t0* must be in kelvin.

Examples

Determine the relative temperature ratio for three temperatures:

```
th = rrtheta([273.15 310.9278 373.15], 0.5, 1.4)
```

```
th =
```

```
    0.9953    1.1330    1.3597
```

Determine the relative temperature ratio for three temperatures and three different heat ratios:

```
th = rrtheta([273.15 310.9278 373.15], 0.5, [1.4 1.35 1.4])
```

```
th =
```

```
    0.9953    1.1263    1.3597
```

Determine the relative temperature ratio for three temperatures at three different conditions:

```
th = rrtheta([273.15 310.9278 373.15], [0.5 1 2], [1.4 1.35 1.4])
```

```
th =
```

```
    0.9953    1.2679    2.3310
```

Assumptions and Limitations

For cases in which total temperature ratio is desired (Mach number is nonzero), the total temperature is calculated assuming perfect gas (with constant molecular weight, constant pressure specific heat, and constant specific heat ratio) and dry air.

References

Aeronautical Vestpocket Handbook, United Technologies Pratt & Whitney, August, 1986

See Also

rrdelta | rrsigma

Introduced in R2006b

Satellite

Satellite object belonging to satellite scenario

Description

Satellite defines a satellite object belonging to a satellite scenario.

Creation

You can create Satellite objects using the `satellite` method of `satelliteScenario`.

Properties

Orbit — Orbit graphic

Orbit object

Orbit object parameters for a satellite, specified as an orbit object. Only these object properties are relevant for this function.

LineColor — Color of orbit







[1,0,0] (default) | RGB triplet | hexadecimal color code | 'r' | 'g' | 'b'


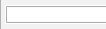
Color of the orbit, specified as an RGB triplet, hexadecimal color code, a color name, or a short name.

For a custom color, specify an RGB triplet or a hexadecimal color code.

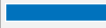
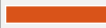





- An RGB triplet is a three-element row vector whose elements specify the intensities of the red, green, and blue components of the color. The intensities must be in the range [0,1]; for example, [0.4 0.6 0.7].
- A hexadecimal color code is a character vector or a string scalar that starts with a hash symbol (#) followed by three or six hexadecimal digits, which can range from 0 to F. The values are not case sensitive. Thus, the color codes '#FF8800', '#ff8800', '#F80', and '#f80' are equivalent.

Alternatively, you can specify some common colors by name. This table lists the named color options, the equivalent RGB triplets, and hexadecimal color codes.

Color Name	Short Name	RGB Triplet	Hexadecimal Color Code	Appearance
'red'	'r'	[1 0 0]	'#FF0000'	
'green'	'g'	[0 1 0]	'#00FF00'	
'blue'	'b'	[0 0 1]	'#0000FF'	
'cyan'	'c'	[0 1 1]	'#00FFFF'	
'magenta'	'm'	[1 0 1]	'#FF00FF'	
'yellow'	'y'	[1 1 0]	'#FFFF00'	

Color Name	Short Name	RGB Triplet	Hexadecimal Color Code	Appearance
'black'	'k'	[0 0 0]	'#000000'	
'white'	'w'	[1 1 1]	'#FFFFFF'	
'none'	Not applicable	Not applicable	Not applicable	No color

Here are the RGB triplets and hexadecimal color codes for the default colors MATLAB uses in many types of plots.

RGB Triplet	Hexadecimal Color Code	Appearance
[0 0.4470 0.7410]	'#0072BD'	
[0.8500 0.3250 0.0980]	'#D95319'	
[0.9290 0.6940 0.1250]	'#EDB120'	
[0.4940 0.1840 0.5560]	'#7E2F8E'	
[0.4660 0.6740 0.1880]	'#77AC30'	
[0.3010 0.7450 0.9330]	'#4DBEEE'	
[0.6350 0.0780 0.1840]	'#A2142F'	

Example: 'blue'

Example: [0 0 1]

Example: '#0000FF'

LineWidth — Visual width of orbit

1 (default) | scalar in the range (0, 10)

Visual width of orbit in pixels, specified as a scalar in the range (0, 10).

The line width cannot be thinner than the width of a pixel. If you set the line width to a value that is less than the width of a pixel on your system, the line displays as one pixel wide.

VisibilityMode — Visibility mode of orbit graphic

'inherit' (default) | 'manual'

Visibility mode of orbit graphic, specified as one of these values:

- 'inherit' — Visibility of the graphic matches that of the parent
- 'manual' — Visibility of the graphic is not inherited and is independent of that of the parent

Data Types: char | string

Accesses — Access analysis objects

row vector of Access objects

You can set this property only when calling Satellite. After you call Satellite, this property is read-only.

Access analysis objects, specified as a row vector of Access objects.

MarkerColor — Color of marker





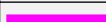
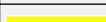
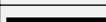

[1 0 0] (default) | RGB triplet | string scalar of color name | character vector of color name

Color of the marker, specified as a comma-separated pair consisting of 'MarkerColor' and either an RGB triplet or a string or character vector of a color name.







For a custom color, specify an RGB triplet or a hexadecimal color code.

- An RGB triplet is a three-element row vector whose elements specify the intensities of the red, green, and blue components of the color. The intensities must be in the range [0, 1]; for example, [0.4 0.6 0.7].
- A hexadecimal color code is a character vector or a string scalar that starts with a hash symbol (#) followed by three or six hexadecimal digits, which can range from 0 to F. The values are not case sensitive. Thus, the color codes '#FF8800', '#ff8800', '#F80', and '#f80' are equivalent.

Alternatively, you can specify some common colors by name. This table lists the named color options, the equivalent RGB triplets, and hexadecimal color codes.

Color Name	Short Name	RGB Triplet	Hexadecimal Color Code	Appearance
'red'	'r'	[1 0 0]	'#FF0000'	
'green'	'g'	[0 1 0]	'#00FF00'	
'blue'	'b'	[0 0 1]	'#0000FF'	
'cyan'	'c'	[0 1 1]	'#00FFFF'	
'magenta'	'm'	[1 0 1]	'#FF00FF'	
'yellow'	'y'	[1 1 0]	'#FFFF00'	
'black'	'k'	[0 0 0]	'#000000'	
'white'	'w'	[1 1 1]	'#FFFFFF'	
'none'	Not applicable	Not applicable	Not applicable	No color

Here are the RGB triplets and hexadecimal color codes for the default colors MATLAB uses in many types of plots.

RGB Triplet	Hexadecimal Color Code	Appearance
[0 0.4470 0.7410]	'#0072BD'	
[0.8500 0.3250 0.0980]	'#D95319'	
[0.9290 0.6940 0.1250]	'#EDB120'	
[0.4940 0.1840 0.5560]	'#7E2F8E'	
[0.4660 0.6740 0.1880]	'#77AC30'	
[0.3010 0.7450 0.9330]	'#4DBEEE'	
[0.6350 0.0780 0.1840]	'#A2142F'	

MarkerSize — Size of marker

10 (default) | positive scalar less than 30

Size of the marker, specified as a comma-separated pair consisting of 'MarkerSize' and a real positive scalar less than 30. The unit is in pixels.

ShowLabel — State of Satellite label visibility

true or 1 (default) | false or 0

State of Satellite label visibility, specified as a comma-separated pair consisting of 'ShowLabel' and numerical or logical value of 1 (true) or 0 (false).

Data Types: logical

LabelFontSize — Font size of Satellite label

15 (default) | positive scalar less than 30

Font size of the Satellite label, specified as a comma-separated pair consisting of 'LabelFontSize' and a positive scalar less than 30.

LabelFontColor — Font color of Satellite label





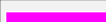
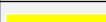


[1,0,0] (default) | RGB triplet | string scalar of color name | character vector of color name

Font color of the Satellitelabel, specified as a comma-separated pair consisting of 'LabelFontColor' and either an RGB triplet or a string or character vector of a color name.








For a custom color, specify an RGB triplet or a hexadecimal color code.

- An RGB triplet is a three-element row vector whose elements specify the intensities of the red, green, and blue components of the color. The intensities must be in the range [0, 1]; for example, [0.4 0.6 0.7].
- A hexadecimal color code is a character vector or a string scalar that starts with a hash symbol (#) followed by three or six hexadecimal digits, which can range from 0 to F. The values are not case sensitive. Thus, the color codes '#FF8800', '#ff8800', '#F80', and '#f80' are equivalent.

Alternatively, you can specify some common colors by name. This table lists the named color options, the equivalent RGB triplets, and hexadecimal color codes.

Color Name	Short Name	RGB Triplet	Hexadecimal Color Code	Appearance
'red'	'r'	[1 0 0]	'#FF0000'	
'green'	'g'	[0 1 0]	'#00FF00'	
'blue'	'b'	[0 0 1]	'#0000FF'	
'cyan'	'c'	[0 1 1]	'#00FFFF'	
'magenta'	'm'	[1 0 1]	'#FF00FF'	
'yellow'	'y'	[1 1 0]	'#FFFF00'	
'black'	'k'	[0 0 0]	'#000000'	
'white'	'w'	[1 1 1]	'#FFFFFF'	
'none'	Not applicable	Not applicable	Not applicable	No color

Here are the RGB triplets and hexadecimal color codes for the default colors MATLAB uses in many types of plots.

RGB Triplet	Hexadecimal Color Code	Appearance
[0 0.4470 0.7410]	'#0072BD'	
[0.8500 0.3250 0.0980]	'#D95319'	
[0.9290 0.6940 0.1250]	'#EDB120'	
[0.4940 0.1840 0.5560]	'#7E2F8E'	
[0.4660 0.6740 0.1880]	'#77AC30'	
[0.3010 0.7450 0.9330]	'#4DBEEE'	
[0.6350 0.0780 0.1840]	'#A2142F'	

Name — Satellite name

"Satellite *idx*" (default) | string scalar | string vector | character vector | cell array of character vectors

You can set this property only when calling `Satellite`. After you call `Satellite`, this property is read-only.

Satellite name, specified as a comma-separated pair consisting of 'Name' and a string scalar, string vector, character vector or a cell array of character vectors.

- If only one Satellite is added, specify Name as a string scalar or a character vector.
- If multiple Satellites are added, specify Name as a string vector or a cell array of character vectors. The number of elements in the string vector or cell array must be equal to the number of satellites being added.

In the default value, *idx* is the count of the Satellite added by the `Satellite` object function. If another Satellite of the same name exists, a suffix *_idx₂* is added, where *idx₂* is an integer that is incremented by 1 starting from 1 until the name duplication is resolved.

Data Types: char | string

ID — Satellite ID assigned by simulator

real positive scalar

This property is set internally by the simulator and is read-only.

Satellite ID assigned by the simulator, specified as a positive scalar.

ConicalSensors — Conical sensors

row vector of conical sensors

You can set this property only when calling `conicalSensor`. After you call `conicalSensor`, this property is read-only.

Conical sensors attached to the Satellite, specified as a row vector of conical sensors.

Gimbals — Gimbals

row vector of Gimbal objects

You can set this property only when calling `gimbal`. After you call `gimbal`, this property is read-only.

Gimbals attached to the Satellite, specified as the comma-separated pair consisting of 'Gimbals' and a row vector of Gimbal objects.

OrbitPropagator — Name of orbit propagator

"sgp4" (default) | "two-body-keplerian" | "sdp4" | "ephemeris"

You can set this property when calling `satellite` only. After you call `satellite`, this property is read-only.

Name of the orbit propagator used for propagating satellite position and velocity, specified as the comma-separated pair consisting of 'OrbitPropagator' and either "two-body-keplerian", "sgp4", "sdp4", or "ephemeris".

Dependencies

OrbitPropagator is not available for ephemeris data inputs (`timetable` or `timeseries`). In these cases, `satellite` ignores this name-value pair.

Data Types: `string` | `char`

Object Functions

<code>access</code>	Add access analysis objects to satellite scenario
<code>states</code>	Position and velocity of satellite
<code>conicalSensor</code>	Add conical sensor to satellite scenario
<code>pointAt</code>	Target at which entity must be pointed
<code>gimbal</code>	Add gimbal to satellite or ground station
<code>show</code>	Show object in satellite scenario viewer
<code>aer</code>	Calculate azimuth angle, elevation angle, and range in NED frame from another satellite or ground station
<code>hide</code>	Hides satellite scenario entity from viewer
<code>groundTrack</code>	Add ground track object to satellite in scenario
<code>orbitalElements</code>	Orbital elements of satellites in scenario

See Also**Objects**

`access` | `groundStation` | `satelliteScenario` | `satelliteScenarioViewer`

Functions

`hide` | `play` | `show`

Topics

"Satellite Scenario Key Concepts" on page 2-61

Introduced in R2021a

satellite

Add satellites to satellite scenario

Syntax

```
satellite(scenario,tlefile)
satellite(scenario,semimajoraxis,eccentricity,inclination,RAAN,
argofperiapsis,trueanomaly)
satellite(scenario,positiontable)
satellite(scenario,positiontable,velocitytable)
satellite(scenario,positiontimeseries)
satellite(scenario,positiontimeseries,velocitytimeseries)
satellite( ____,Name,Value)
sat = satellite( ____ )
```

Description

`sat = satellite(scenario,tlefile)` adds a `Satellite` object from TLE file to the satellite scenario specified by `scenario`, specified as a string scalar or character vector. The yaw (z) axes of the satellites point toward nadir, and the roll (x) axes of the satellites align with their respective inertial velocity vectors.

`satellite(scenario,semimajoraxis,eccentricity,inclination,RAAN,argofperiapsis,trueanomaly)` adds a `Satellite` object from Keplerian elements defined in the Geocentric Celestial Reference Frame (GCRF) to the satellite scenario.

`satellite(scenario,positiontable)` adds a `Satellite` object from position data specified in `positiontable` (`timetable` object) to the scenario. This function creates a `Satellite` with `OrbitPropagator="ephemeris"`.

`satellite(scenario,positiontable,velocitytable)` adds a `Satellite` object from position data specified in `positiontable` (`timetable` object) and velocity data specified in `velocitytable` (`timetable` object) to the scenario. This function creates a `Satellite` with `OrbitPropagator="ephemeris"`.

`satellite(scenario,positiontimeseries)` adds a `Satellite` object from position data specified in `positiontimeseries` (`timeseries` object). This function creates a `Satellite` with `OrbitPropagator="ephemeris"`.

`satellite(scenario,positiontimeseries,velocitytimeseries)` adds a `Satellite` object to the scenario from position (in meters) data specified in `positiontimeseries` (`timeseries` object) and velocity (in meters/second) data specified in `velocitytimeseries` (`timeseries` object). This function creates a `Satellite` with `OrbitPropagator="ephemeris"`.

`satellite(____,Name,Value)` specifies options using one or more name-value arguments in addition to any input argument combination from previous syntaxes. For example, `('Name','satellit1')` specifies the name of the satellite as `'satellit1'`.

`sat = satellite(____)` returns a vector of handles to the added satellites. Specify any input argument combination from previous syntaxes.

Examples

Add Four Satellites from Position Timetable and Visualize Their Trajectories

Add four satellites to the satellite scenario from a position timetable to a satellite scenario and visualize their trajectories.

Create a default satellite scenario object.

```
sc = satelliteScenario;
```

Load a satellite ephemeris timetable, assuming the data is in the GCRF coordinate frame.

```
load("timetableSatelliteTrajectory.mat","positionTT");
```

Add the satellites to the scenario.

```
sat = satellite(sc,positionTT);
```

Visualize the trajectories of the satellites.

```
play(sc);
```

Add Four Satellites from Position and Velocity Timetable and Visualize Their Trajectories

Add four satellites to the satellite scenario from position and velocity timetables in the Earth Centered Earth Fixed (ECEF) frame and visualize their trajectories.

Create a default satellite scenario object.

```
sc = satelliteScenario;
```

Load a satellite ephemeris timetable, assuming the data is in the ECEF coordinate frame.

```
load("timetableSatelliteTrajectory.mat","positionTT","velocityTT");
```

Add the satellites to the scenario.

```
sat = satellite(sc,positionTT,velocityTT,"CoordinateFrame","ecef")
```

Visualize the trajectories of the satellites.

```
play(sc);
```

Add Ground stations to Scenario and Visualize Access Intervals

Create satellite scenario and add ground stations from latitudes and longitudes.

```
startTime = datetime(2020, 5, 1, 11, 36, 0);
stopTime = startTime + days(1);
sampleTime = 60;
sc = satelliteScenario(startTime, stopTime, sampleTime);
lat = [10];
```

```
lon = [-30];
gs = groundStation(sc, lat, lon);
```

Add satellites using Keplerian elements.

```
semiMajorAxis = 10000000;
eccentricity = 0;
inclination = 10;
rightAscensionOfAscendingNode = 0;
argumentOfPeriapsis = 0;
trueAnomaly = 0;
sat = satellite(sc, semiMajorAxis, eccentricity, inclination, ...
    rightAscensionOfAscendingNode, argumentOfPeriapsis, trueAnomaly);
```

Add access analysis to the scenario and obtain the table of intervals of access between the satellite and the ground station.

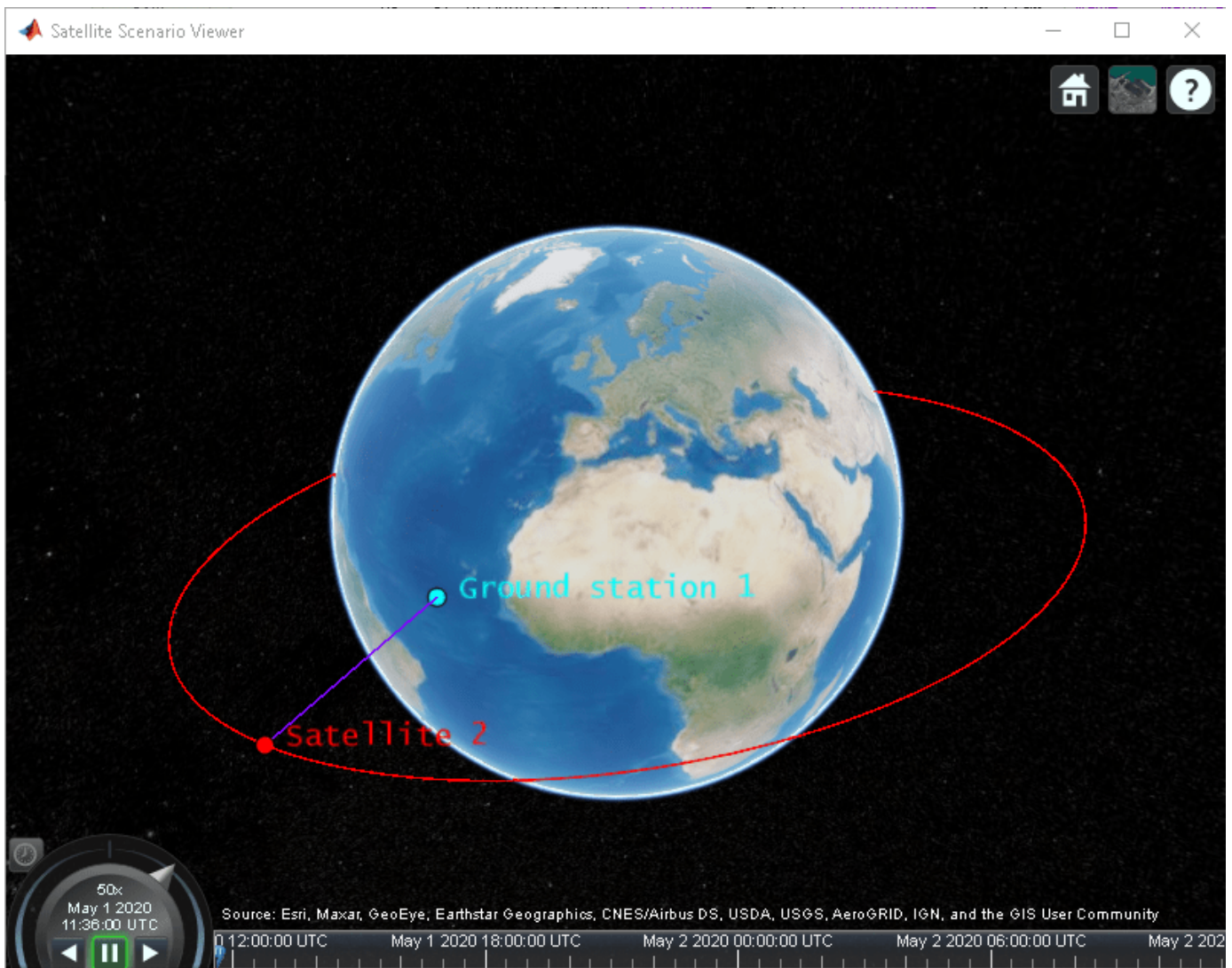
```
ac = access(sat, gs);
intvls = accessIntervals(ac)
```

intvls=8x8 table

Source	Target	IntervalNumber	StartTime	EndTime
"Satellite 2"	"Ground station 1"	1	01-May-2020 11:36:00	01-May-2020
"Satellite 2"	"Ground station 1"	2	01-May-2020 14:20:00	01-May-2020
"Satellite 2"	"Ground station 1"	3	01-May-2020 17:27:00	01-May-2020
"Satellite 2"	"Ground station 1"	4	01-May-2020 20:34:00	01-May-2020
"Satellite 2"	"Ground station 1"	5	01-May-2020 23:41:00	02-May-2020
"Satellite 2"	"Ground station 1"	6	02-May-2020 02:50:00	02-May-2020
"Satellite 2"	"Ground station 1"	7	02-May-2020 05:59:00	02-May-2020
"Satellite 2"	"Ground station 1"	8	02-May-2020 09:06:00	02-May-2020

Play the scenario to visualize the ground stations.

```
play(sc)
```



Add Satellites to Scenario Using Keplerian Elements

Create a satellite scenario with a start time of 02-June-2020 8:23:00 AM UTC, and the stop time set to one day later. Set the simulation sample time to 60 seconds.

```
startTime = datetime(2020,6,02,8,23,0);
stopTime = startTime + days(1);
sampleTime = 60;
sc = satelliteScenario(startTime,stopTime,sampleTime);
```

Add two satellites to the scenario using their Keplerian elements.

```
semiMajorAxis = [10000000; 15000000];
eccentricity = [0.01; 0.02];
inclination = [0; 10];
rightAscensionOfAscendingNode = [0; 15];
```

```
argumentOfPeriapsis = [0; 30];
trueAnomaly = [0; 20];

sat = satellite(sc, semiMajorAxis, eccentricity, inclination, ...
    rightAscensionOfAscendingNode, argumentOfPeriapsis, trueAnomaly)

sat =
    1×2 Satellite array with properties:

        Name
        ID
        ConicalSensors
        Gimbals
        Transmitters
        Receivers
        Accesses
        GroundTrack
        Orbit
        OrbitPropagator
        MarkerColor
        MarkerSize
        ShowLabel
        LabelFontSize
        LabelFontColor
```

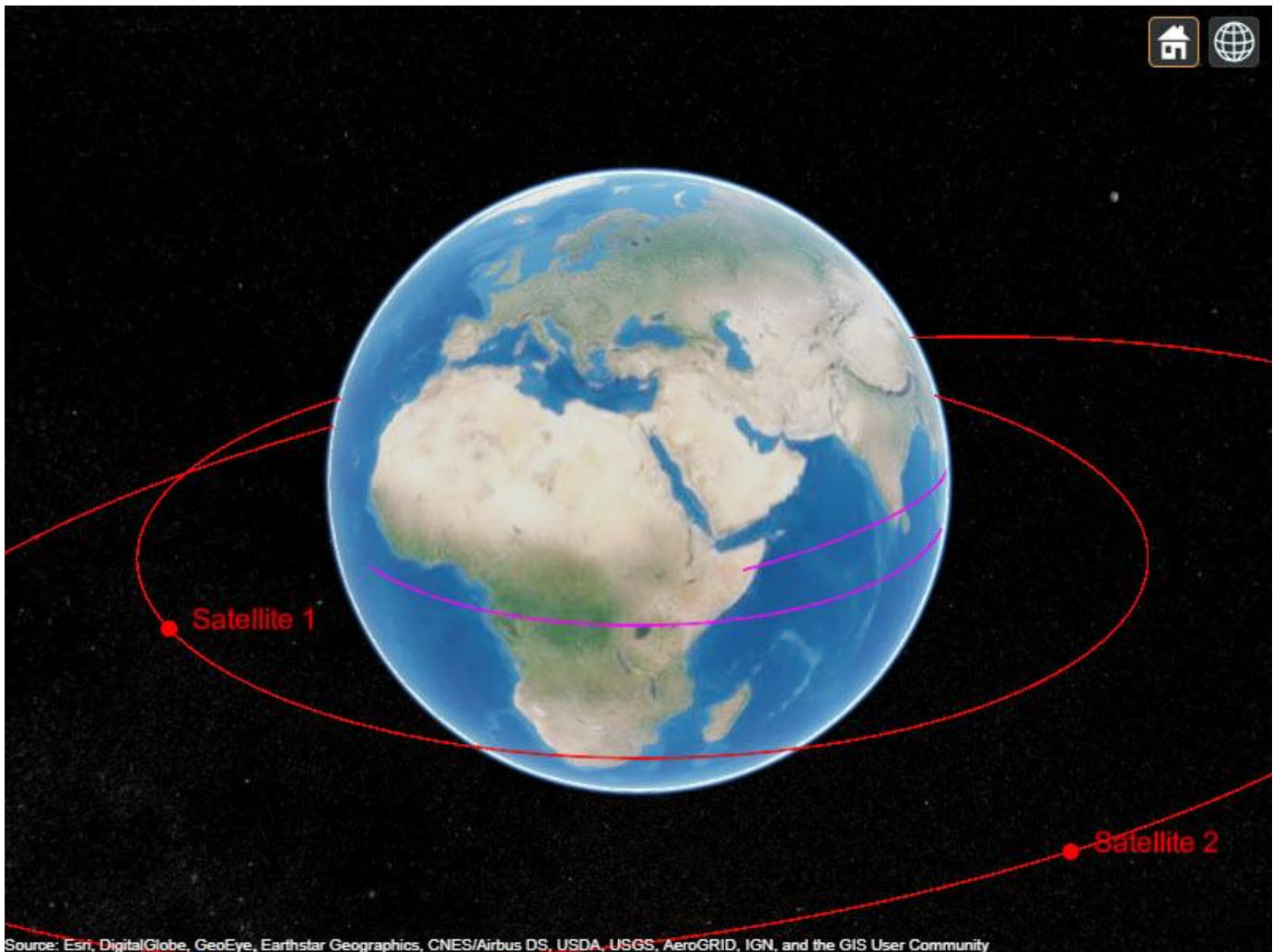
View the satellites in orbit and the ground tracks over one hour.

```
show(sat)
groundTrack(sat, 'LeadTime', 3600)

ans=1×2 object
    1×2 GroundTrack array with properties:

        LeadTime
        TrailTime
        LineWidth
        TrailLineColor
        LeadLineColor
        VisibilityMode
```

```
play(sc)
```



Input Arguments

scenario — Satellite scenario

satelliteScenario object

Satellite scenario, specified as a satelliteScenario object.

tfile — Name of TLE file

character vector | string scalar

Name of a TLE file, specified as a character vector or a string scalar. The TLE file must exist in the current directory, exist in a directory on the MATLAB path, or include a full or relative path to a file.

For more information on TLE files, see “Two Line Element (TLE) Files” on page 2-66.

Data Types: char | string

semimajoraxis, eccentricity, inclination, RAAN, argofperiapsis, trueanomaly — Keplerian elements defined in GCRF

comma-separated list of vectors

Keplerian elements defined in the GCRF, specified as a comma-separated list of vectors. The Keplerian elements are:

- **semimajoraxis** - This vector defines the semimajor axis of the orbit of the satellite. Each value is equal to half of the longest diameter of the orbit.
- **eccentricity** - This vector defines the shape of the orbit of the satellite.
- **inclination** - This vector defines the angle between the orbital plane and the xy-plane of the GCRF for each satellite.
- **RAAN** (right ascension of ascending node) - This element defines the angle between the xy-plane of the GCRF and the direction of the ascending node, as seen from the Earth's center of mass for each satellite. The ascending node is the location where the orbit crosses the xy-plane of the GCRF and goes above the plane.
- **argofperiapsis** (argument of periapsis) - This vector defines the angle between the direction of the ascending node and the periapsis, as seen from the Earth's center of mass. Periapsis is the location on the orbit that is closest to the Earth's center of mass for each satellite.
- **trueanomaly** - This vector defines the angle between the direction of the periapsis and the current location of the satellite, as seen from the Earth's center of mass for each satellite.

For more information on Keplerian elements, see “Orbital Elements” on page 2-65.

positiontable — Position data

timetable | table

Position data in meters, specified as a timetable created using the `timetable` function. `positiontable` has exactly one monotonically increasing column of `rowTimes` (datetime or duration values) and one or more columns of variables, where each column contains an individual satellite position over time.

If `rowTimes` values are of type `duration`, time values are measured relative to the current scenario `StartTime` property. The timetable `VariableNames` are used by default if no names are provided as an input. Satellite states are assumed to be in the GCRF unless a `CoordinateFrame` name-value argument is provided. States are held constant in GCRF for scenario timesteps outside of the time range of `positiontable`.

Data Types: `table` | `timetable`

velocitytable — Velocity data

timetable | table

Velocity data in meters/second, specified as a timetable created using the `timetable` function. `velocitytable` has exactly one monotonically increasing column of `rowTimes` (datetime or duration values) and one or more columns of variables, where each column contains an individual satellite position over time.

If `rowTimes` values are of type `duration`, time values are measured relative to the current scenario `StartTime` property. The timetable `VariableNames` are used by default if no names are provided as an input. Satellite states are assumed to be in the GCRF unless a `CoordinateFrame` name-value argument is provided. States are held constant in GCRF for scenario timesteps outside of the time range of `velocitytable`.

Data Types: `table` | `timetable`

positiontimeseries — Position data

`timeseries` object | `tscollection` object

Position data in meters, specified as a `timeseries` object or a `tscollection` object.

- If the `Data` property of the `timeseries` or `tscollection` object has two dimensions, one dimension must equal 3, and the other dimension must align with the orientation of the time vector.
- If the `Data` property of the `timeseries` or `tscollection` has three dimensions, one dimension must equal 3, either the first or the last dimension must align with the orientation of the time vector, and the remaining dimension defines the number of satellites in the ephemeris.

When `timeseries.TimeInfo.StartDate` is empty, time values are measured relative to the current scenario `StartTime` property. The `timeseries` `Name` property (if defined) is used by default if no names are provided as inputs. Satellite states are assumed to be in the GCRF unless a `CoordinateFrame` name-value pair is provided. States are held constant in GCRF for scenario timesteps outside of the time range of `positiontimeseries`.

Data Types: `timeseries` | `tscollection`

velocitytimeseries — Velocity data

`timeseries` object | `tscollection` object

Velocity data in meters/second, specified as a `timeseries` object or a `tscollection` object.

- If the `Data` property of the `timeseries` or `tscollection` object has two dimensions, one dimension must equal 3, and the other dimension must align with the orientation of the time vector.
- If the `Data` property of the `timeseries` or `tscollection` has three dimensions, one dimension must equal 3, either the first or the last dimension must align with the orientation of the time vector, and the remaining dimension defines the number of satellites in the ephemeris.

When `timeseries.TimeInfo.StartDate` is empty, time values are measured relative to the current scenario `StartTime` property. The `timeseries` `Name` property (if defined) is used by default if no names are provided as inputs. Satellite states are assumed to be in the GCRF unless a `CoordinateFrame` name-value pair is provided. States are held constant in GCRF for scenario timesteps outside of the time range of `velocitytimeseries`.

Data Types: `timeseries` | `tscollection`

Name-Value Pair Arguments

Specify optional comma-separated pairs of `Name`, `Value` arguments. `Name` is the argument name and `Value` is the corresponding value. `Name` must appear inside quotes. You can specify several name and value pair arguments in any order as `Name1, Value1, ..., NameN, ValueN`.

Example: `'Name', 'MySatellite'` sets the satellite name to `'MySatellite'`.

Viewer — Satellite scenario viewer

(default) | row vector of all viewer objects | row vector of `satelliteScenarioViewer` objects

Satellite scenario viewer, specified as a row vector of `satelliteScenarioViewer` objects.

Data Types: char | string

Name — satellite name

"satellite *idx*" (default) | string scalar | string vector | character vector | cell array of character vectors

You can set this property only when calling `satellite`. After you call `satellite`, this property is read-only.

satellite name, specified as a comma-separated pair consisting of 'Name' and a string scalar, string vector, character vector or a cell array of character vectors.

- If only one satellite is added, specify Name as a string scalar or a character vector.
- If multiple satellites are added, specify Name as a string vector or a cell array of character vectors. The number of elements in the string vector or cell array must be equal to the number of satellites being added.

In the default value, *idx* is the count of the satellite added by the `satellite` object function. If another satellite of the same name exists, a suffix *idx*₂ is added, where *idx*₂ is an integer that is incremented by 1 starting from 1 until the name duplication is resolved.

Data Types: char | string

OrbitPropagator — Name of orbit propagator

"sgp4" (default) | "two-body-keplerian" | "sdp4" | "ephemeris"

You can set this property when calling `satellite` only. After you call `satellite`, this property is read-only.

Name of the orbit propagator used for propagating satellite position and velocity, specified as the comma-separated pair consisting of 'OrbitPropagator' and either "two-body-keplerian", "sgp4", "sdp4", or "ephemeris".

Dependencies

OrbitPropagator is not available for ephemeris data inputs (`timetable` or `timeseries`). In these cases, `satellite` ignores this name-value pair.

Data Types: string | char

CoordinateFrame — Satellite state coordinate frame

"inertial" (default) | "ecef" | "geographic"

Satellite state coordinate frame, specified as the comma-separated pair consisting of 'CoordinateFrame' and one of these values:

- "inertial" — For `timeseries` or `timetable` data, specifying this value accepts the position and velocity in the GCRF frame.
- "ecef" — For `timeseries` or `timetable` data, specifying this value accepts the position and velocity in the ECEF frame.
- "geographic" — For `timeseries` or `timetable` data, specifying this value accepts the position [*lat*, *lon*, *altitude*], where *lat* and *lon* are latitude and longitude in degrees, and *altitude* is the height above the World Geodetic System 84 (WGS 84) ellipsoid in meters.

Velocity is in the local NED frame.

Dependencies

To enable this name value argument, ephemeris data inputs (`timetable` or `timeseries`).

Data Types: `string` | `char`

Output Arguments**sat — Satellite in the scenario**

Satellite object

Satellite in the scenario, returned as a `Satellite` object belonging to the satellite scenario specified by `scenario`.

You can modify the `Satellite` object by changing its property values.

See Also**Objects**

`satelliteScenario` | `satelliteScenarioViewer`

Functions

`access` | `hide` | `orbitalElements` | `play` | `show`

Topics

“Satellite Scenario Key Concepts” on page 2-61

“Satellite Scenario Overview” on page 2-69

Introduced in R2021a

satelliteScenario

Create satellite scenario object

Description

The `satelliteScenario` object represents a 3-D arena consisting of satellites, ground stations, and the interactions between them. Use this object to model satellite constellations, model ground station networks, perform access analyses between the satellites and the ground stations, and visualize the results.

Creation

Syntax

```
sc = satelliteScenario
sc = satelliteScenario(startTime, stopTime, sampleTime)
```

Description

`sc = satelliteScenario` creates a default satellite scenario object.

`sc = satelliteScenario(startTime, stopTime, sampleTime)` sets the `StartTime`, `StopTime`, and `SampleTime` properties to the values of `startTime`, `stopTime`, and `sampleTime` respectively.

Properties

StartTime — Start time of satellite scenario simulation in UTC

current time or earliest epoch defined in TLE data (default) | `datetime` scalar

Start time of the satellite scenario simulation in Universal Time Coordinated (UTC), specified as a `datetime` scalar. If you specify the `StartTime`, `StopTime`, or `SampleTime` properties, the object no longer updates `StartTime` property with further additions of satellites from TLE files.

Example: `datetime(2020,5,11,12,35,38);`

Data Types: `datetime`

StopTime — Stop time of satellite scenario simulation in UTC

`StartTime` + longest orbital period among the satellites in the scenario (default) | `datetime` scalar

Stop time of the satellite scenario simulation in UTC, specified as a `datetime` scalar. If you specify the `StartTime`, `StopTime`, or `SampleTime` properties, the object no longer updates `StartTime` property with further additions of satellites from TLE files.

Example: `datetime(2020,5,11,12,35,38);`

Data Types: `datetime`

SampleTime — Sample time of satellite scenario simulation

$(\text{StopTime} - \text{StartTime})/99$ (default) | real-valued scalar

Sample time of the satellite scenario simulation, specified as a real-valued scalar. If you specify the `StartTime`, `StopTime`, or `SampleTime` properties, the object no longer updates, the `SampleTime` property updated with further additions of satellites from TLE files.

Data Types: `double`

Satellites – Satellites in the scenario

row vector of `Satellite` objects

This property is read-only.

Satellites in the scenario, returned as a vector of `Satellite` objects. To create a `Satellite` object and add it to the satellite scenario, see the `satellite` object function.

GroundStations – Ground stations in scenario

row vector of `GroundStation` objects

This property is read-only.

Ground stations in the scenario, returned as a row vector of `GroundStation` objects. To create a `GroundStation` object and add it to the satellite scenario, see the `groundStation` object function.

Autoshow – Graphics shown automatically

1 or true (default) | 0 or false

Option to automatically show graphics, specified as a numeric or logical value of 1 (`true`) or 0 (`false`). This property determines if entities added to the scenario are automatically shown in an open `satelliteScenarioViewer`.

Object Functions

<code>groundStation</code>	Add ground station to satellite scenario
<code>satellite</code>	Add satellites to satellite scenario
<code>satelliteScenarioViewer</code>	Create viewer for satellite scenario
<code>play</code>	Play satellite scenario simulation results on viewer

Examples

Create Satellite Scenario with Custom Start and Stop Times

Specify the start time in the current time zone as yesterday. The simulation lasts for half a day.

```
startTime = datetime("yesterday", "TimeZone", "local");
stopTime = startTime + days(0.5);
```

Specify the sample time as 60 seconds. Create a satellite scenario object, specifying the start time, stop time, and sample time.

```
sampleTime = 60;
sc = satelliteScenario(startTime, stopTime, sampleTime)
```

```
sc =
    satelliteScenario with properties:
```

```
    StartTime: 22-Feb-2021 05:00:00
```

```
StopTime: 22-Feb-2021 17:00:00
SampleTime: 60
Viewers: [0x0 matlabshared.satellitescenario.Viewer]
Satellites: []
GroundStations: []
AutoShow: 1
```

Add Satellites to Scenario Using Keplerian Elements

Create a satellite scenario with a start time of 02-June-2020 8:23:00 AM UTC, and the stop time set to one day later. Set the simulation sample time to 60 seconds.

```
startTime = datetime(2020,6,02,8,23,0);
stopTime = startTime + days(1);
sampleTime = 60;
sc = satelliteScenario(startTime,stopTime,sampleTime);
```

Add two satellites to the scenario using their Keplerian elements.

```
semiMajorAxis = [10000000; 15000000];
eccentricity = [0.01; 0.02];
inclination = [0; 10];
rightAscensionOfAscendingNode = [0; 15];
argumentOfPeriapsis = [0; 30];
trueAnomaly = [0; 20];
```

```
sat = satellite(sc, semiMajorAxis, eccentricity, inclination, ...
    rightAscensionOfAscendingNode, argumentOfPeriapsis, trueAnomaly)
```

```
sat =
    1x2 Satellite array with properties:
```

```
Name
ID
ConicalSensors
Gimbals
Transmitters
Receivers
Accesses
GroundTrack
Orbit
OrbitPropagator
MarkerColor
MarkerSize
ShowLabel
LabelFontSize
LabelFontColor
```

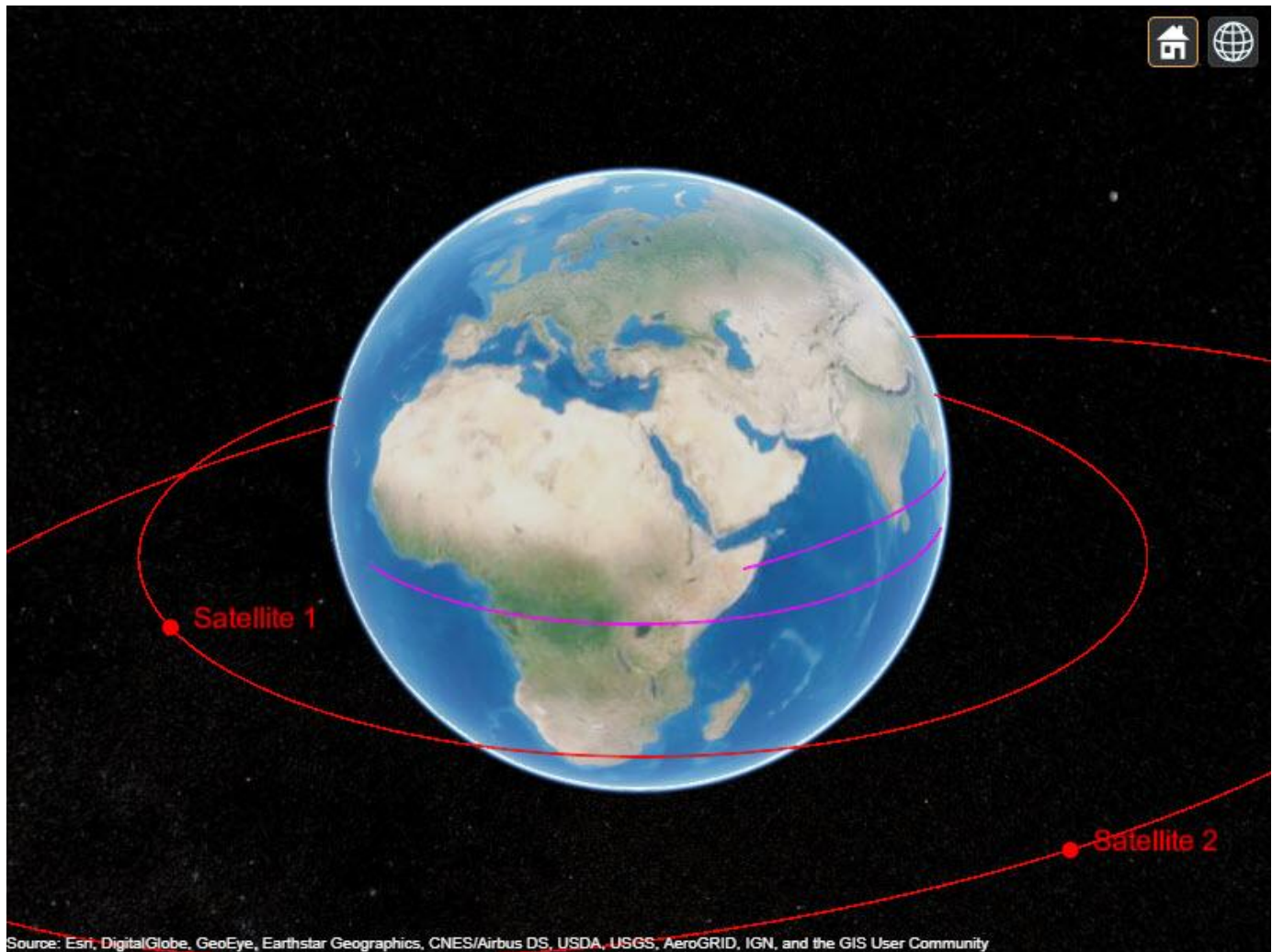
View the satellites in orbit and the ground tracks over one hour.

```
show(sat)
groundTrack(sat, 'LeadTime',3600)

ans=1x2 object
    1x2 GroundTrack array with properties:
```

```
LeadTime  
TrailTime  
LineWidth  
TrailLineColor  
LeadLineColor  
VisibilityMode
```

```
play(sc)
```



Tips

- For correct visualization of all items in the scenario, save either the entire workspace or the scenario containing all the elements.

See Also

Objects

satellite | satelliteScenarioViewer

Functions

access | groundStation | hide | play | show

Topics

“Satellite Scenario Key Concepts” on page 2-61

Introduced in R2021a

satelliteScenarioViewer

Create viewer for satellite scenario

Syntax

```
satelliteScenarioViewer(scenario)
satelliteScenarioViewer(scenario,Name,Value)
v = satelliteScenarioViewer(scenario)
```

Description

`satelliteScenarioViewer(scenario)` creates a 3-D or 2-D satellite scenario viewer for the specified satellite scenario.

Note

- Satellite Scenario Viewer is a 3-D map display and requires hardware graphics support for WebGL™.
-

`satelliteScenarioViewer(scenario,Name,Value)` creates a new viewer using one or more name-value arguments. For example, 'Basemap', 'topographic' bases the scenario on Topographic imagery provided by Esri®.

`v = satelliteScenarioViewer(scenario)` returns the handle to the satellite scenario viewer.

Input Arguments

scenario — Satellite scenario

satelliteScenario object

Satellite scenario, specified as a satelliteScenario object.

Name-Value Pair Arguments

Specify optional comma-separated pairs of **Name**, **Value** arguments. **Name** is the argument name and **Value** is the corresponding value. **Name** must appear inside quotes. You can specify several name and value pair arguments in any order as `Name1,Value1,...,NameN,ValueN`.

Example: 'Basemap', 'topographic' bases the scenario on Topographic imagery provided by Esri.

Name — Name of viewer window

'Satellite Scenario Viewer' (default) | string scalar | character vector

Name of the viewer window, specified as a comma-separated pair consisting of 'Name' and either a string scalar or a character vector.

Data Types: char | string

Position – Viewer window position


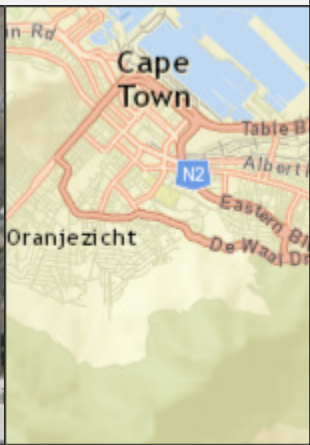

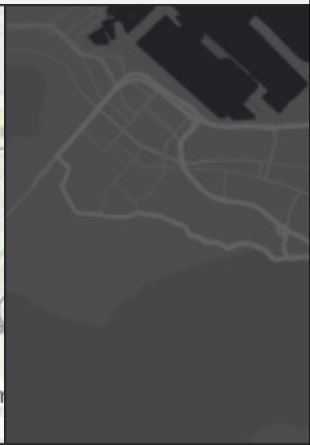
center of the screen (default) | row vector of four elements

Size and location of the satellite scenario window in pixels, specified as a row vector of four elements. The elements of the vector are [left bottom width height]. In the default case, width and height are 800 and 600 pixels, respectively.

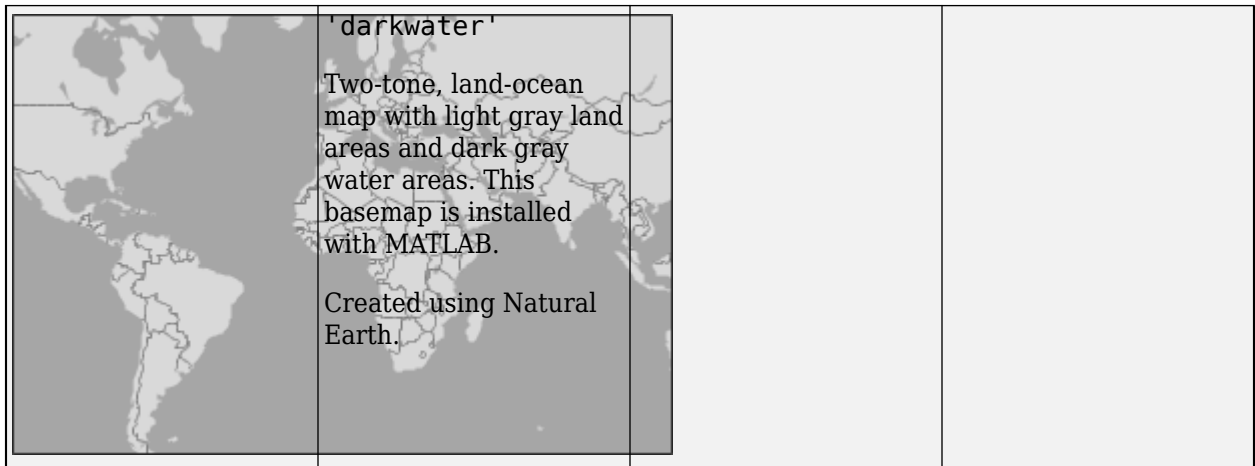
Basemap – Map on which scenario is visualized

'satellite' (default) | 'topographic' | 'streets' | 'streets-light' | 'streets-dark' | 'darkwater' | 'grayland' | 'bluegreen' | 'colorterrain' | 'grayterrain' | 'landcover'

Map on which scenario is visualized, specified as a comma-separated pair consisting of 'Basemap' and one of the values specified in this table:

	<p>'satellite'</p> <p>Full global basemap composed of high-resolution satellite imagery.</p> <p>Hosted by Esri.</p> <p>Earthstar Geograph CNES/Airbus DS</p>		<p>'streets'</p> <p>General-purpose road map that emphasizes accurate, legible styling of roads and transit networks.</p> <p>Hosted by Esri.</p> <p>Esri South Africa, HERE, Garmin, NGA, USGS</p>
	<p>'topographic'</p> <p>General-purpose map with styling to depict topographic features.</p> <p>Hosted by Esri.</p> <p>Esri South Africa, HERE, Garmin, USGS, NGA</p>		<p>'streets-dark'</p> <p>Map designed to provide geographic context while highlighting user data on a dark background.</p> <p>Hosted by Esri.</p> <p>Esri, HERE, Garmin, NGA, USGS</p>

	<p>'landcover'</p> <p>Map that combines satellite-derived land cover data, shaded relief, and ocean-bottom relief. The light, natural palette is suitable for thematic and reference maps.</p> <p>Created using Natural Earth.</p>		<p>'streets-light'</p> <p>Map designed to provide geographic context while highlighting user data on a light background.</p> <p>Hosted by Esri.</p> <p>Esri South Africa, HERE, Garmin, NGA, USGS</p>
	<p>'colorterrain'</p> <p>Shaded relief map blended with a land cover palette. Humid lowlands are green and arid lowlands are brown.</p> <p>Created using Natural Earth.</p>		<p>'grayterrain'</p> <p>Terrain map in shades of gray. Shaded relief emphasizes both high mountains and micro-terrain found in lowlands.</p> <p>Created using Natural Earth.</p>
	<p>'bluegreen'</p> <p>Two-tone, land-ocean map with light green land areas and light blue water areas.</p> <p>Created using Natural Earth.</p>		<p>'grayland'</p> <p>Two-tone, land-ocean map with gray land areas and white water areas.</p> <p>Created using Natural Earth.</p>



All basemaps except 'darkwater' require Internet access. The 'darkwater' basemap is included with MATLAB and Aerospace Toolbox.

If you do not have consistent access to the Internet, you can download the basemaps created using Natural Earth onto your local system by using the Add-On Explorer. The basemaps hosted by Esri are not available for download.

Alignment of boundaries and region labels are a presentation of the feature provided by the data vendors and do not imply endorsement by The MathWorks®.

Data Types: `char` | `string`

Dimension — Dimension of viewer

'3-D' (default) | '2-D'

Dimension of the viewer, specified as a comma-separated pair consisting of 'Dimension' and either '3-D' or '2-D'.

Data Types: `char` | `string`

PlaybackSpeedMultiplier — Speed of animation

50 (default) | positive scalar

Speed of the animation for the input scenario used by the `play` function, specified as a comma-separated pair consisting of 'PlaybackSpeedMultiplier' and a positive scalar.

CameraReferenceFrame — Reference frame of camera

'ECEF' (default) | 'Inertial'

Reference frame of the camera, specified as a comma-separated pair consisting of 'CameraReferenceFrame' and one of these values:

- 'ECEF' — Earth-Centered Earth-Fixed camera.
- 'Inertial' — Inertially fixed camera.

When you specify 'Inertial', the globe rotates with respect to the camera. When you specify 'ECEF', the camera rotates with the globe.

Dependencies

To enable this name-value argument, set to `Dimension` to '3-D'.

CurrentTime — Current simulation time

StartTime of `satelliteScenario` (default) | `datetime` array

Current simulation time of the viewer, specified as a `datetime` array. This value changes over time when the animation is playing.

Data Types: `datetime`

Output Arguments

v — Satellite scenario viewer

`satelliteScenarioViewer` object

Satellite scenario viewer, returned as a `satelliteScenarioViewer` object.

To specify, query, or visualize satellite scenario viewer details, use these functions:

<code>campos</code>	Set or query camera position.
<code>camheight</code>	Set or query camera height.
<code>camheading</code>	Set or query camera heading angle.
<code>camroll</code>	Set or query camera roll angle.
<code>campitch</code>	Set or query camera pitch angle.
<code>camtarget</code>	Target an object with the camera.
<code>hideAll</code>	Hide all visualizations and animations in the Satellite Viewer.
<code>showAll</code>	Show all visualizations and animations in the Satellite Viewer.

Tips

- To pan the viewer window without rotation, use **Shift + left click + drag**.

See Also

Functions

`access` | `groundStation` | `hide` | `play` | `satellite` | `show`

Topics

"Satellite Scenario Key Concepts" on page 2-61

Introduced in R2021a

saveas (Aero.VirtualRealityAnimation)

Save virtual reality world associated with virtual reality animation object

Syntax

```
saveas(h, filename)
h.saveas(filename)
saveas(h, filename, '-nothumbnail')
h.saveas(filename, '-nothumbnail')
```

Description

`saveas(h, filename)` and `h.saveas(filename)` save the world associated with the virtual reality animation object, `h`, into the `.wrl` file name specified in the `filename` variable. After saving, this function reinitializes the virtual reality animation object from the saved world.

`saveas(h, filename, '-nothumbnail')` and `h.saveas(filename, '-nothumbnail')` suppress creating a thumbnail image used for virtual world preview.

Examples

Save the world associated with `h`.

```
h = Aero.VirtualRealityAnimation;
h.VRWorldFilename = [matlabroot, '/toolbox/aero/astdemos/asttkoff.wrl'];
copyfile(h.VRWorldFilename, [tempdir, 'asttkoff.wrl'], 'f');
h.VRWorldFilename = [tempdir, 'asttkoff.wrl'];
h.initialize();
h.saveas([tempdir, 'my_asttkoff.wrl']);
```

Introduced in R2007b

setCoefficient

Class: Aero.FixedWing

Package: Aero

Set coefficient value for Aero.FixedWing object

Syntax

```
aircraft = setCoefficient(aircraft,stateOutput,stateVariable,value)
aircraft = setCoefficient(__,Name,Value)
```

Description

`aircraft = setCoefficient(aircraft,stateOutput,stateVariable,value)` sets the coefficient value `value` to the coefficient specified by `stateOutput` and `stateVariable` and returns the modified object `aircraft`.

`aircraft = setCoefficient(__,Name,Value)` sets the coefficient value using one or more `Name,Value` pair arguments.

Input Arguments

aircraft — Aero.FixedWing object

scalar

Aero.FixedWing object, specified as a scalar.

stateOutput — Valid state output

vector of strings | character array

Valid state output, specified in a vector of strings or character array. For more information, see Aero.FixedWing.Coefficient.

Data Types: string | char

stateVariable — Valid state output

vector of strings | character array

Valid state variable, specified in a vector of strings or character array. Valid state variables depend on the coefficients defined on the object. For more information, see Aero.FixedWing.State.

Data Types: string | char

value — Simulink.LookupTable object or numeric constant

vector of cells

Simulink.LookupTable object or numeric constant, specified as a vector of cells where each cell is a Simulink.LookupTable object or numeric constant. For more information on coefficient values, see Aero.FixedWing.Coefficient.

Data Types: string | char

Name-Value Pair Arguments

Specify optional comma-separated pairs of `Name`, `Value` arguments. `Name` is the argument name and `Value` is the corresponding value. `Name` must appear inside quotes. You can specify several name and value pair arguments in any order as `Name1, Value1, ..., NameN, ValueN`.

Example: `'AddVariable', 'on'`

Component — Component name

string

Component name, specified as a string. Valid component names depend on the object properties and all subcomponents on the object. The default component name is the current object.

Data Types: `char` | `string`

AddVariable — Option to add state variable

`off` (default) | `on`

Option to add state variable if desired state variable is missing, specified as:

- `'on'` — Add a state variable.
- `'off'` — Do not add a state variable.

Data Types: `logical`

Output Arguments

aircraft — Modified Aero.FixedWing object

scalar

Modified `Aero.FixedWing` object with the modified coefficients at the specified locations, returned as a scalar.

Examples

Set Coefficient for Aero.FixedWing Object

Set a coefficient on a `Aero.FixedWing` object.

```
C182 = astC182();
C182 = setCoefficient(C182, "CD", "Alpha", {5})
```

C182 =

FixedWing with properties:

```
ReferenceArea: 174
ReferenceSpan: 36
ReferenceLength: 4.9000
Coefficients: [1x1 Aero.FixedWing.Coefficient]
DegreesOfFreedom: "6DOF"
Surfaces: [1x3 Aero.FixedWing.Surface]
Thrusts: [1x1 Aero.FixedWing.Thrust]
AspectRatio: 7.4483
```



```

    UnitSystem: "English (ft/s)"
    AngleSystem: "Radians"
    TemperatureSystem: "Fahrenheit"
    Properties: [1x1 Aero.Aircraft.Properties]

```

Set Vector of Coefficients for FixedWing.Control Object

Set a vector of coefficients on a FixedWing.Control object.

```

C182 = astC182();
C182 = setCoefficient(C182, ["CY"; "Cm"], ["Zero"; "Alpha"], {5; Simulink.LookupTable})

```

C182 =

FixedWing with properties:

```

    ReferenceArea: 174
    ReferenceSpan: 36
    ReferenceLength: 4.9000
    Coefficients: [1x1 Aero.FixedWing.Coefficient]
    DegreesOfFreedom: "6DOF"
    Surfaces: [1x3 Aero.FixedWing.Surface]
    Thrusts: [1x1 Aero.FixedWing.Thrust]
    AspectRatio: 7.4483
    UnitSystem: "English (ft/s)"
    AngleSystem: "Radians"
    TemperatureSystem: "Fahrenheit"
    Properties: [1x1 Aero.Aircraft.Properties]

```

Set Coefficient on Component in Aero.FixedWing Object

Set a coefficient on a component within an Aero.FixedWing object.

```

C182 = astC182();
C182 = setCoefficient(C182, "CD", "Elevator", {5}, "Component", "Elevator")

```

C182 =

FixedWing with properties:

```

    ReferenceArea: 174
    ReferenceSpan: 36
    ReferenceLength: 4.9000
    Coefficients: [1x1 Aero.FixedWing.Coefficient]
    DegreesOfFreedom: "6DOF"
    Surfaces: [1x3 Aero.FixedWing.Surface]
    Thrusts: [1x1 Aero.FixedWing.Thrust]
    AspectRatio: 7.4483
    UnitSystem: "English (ft/s)"
    AngleSystem: "Radians"

```

```
TemperatureSystem: "Fahrenheit"  
Properties: [1x1 Aero.Aircraft.Properties]
```

Limitations

When used with `Simulink.LookupTable` objects, this method requires a Simulink license.

See Also

`Aero.FixedWing` | `Simulink.LookupTable` | `getCoefficient`

Introduced in R2021a

setCoefficient

Class: Aero.FixedWing.Coefficient

Package: Aero

Set coefficient values for fixed-wing coefficient object

Syntax

```
fixedWingCoefficient = setCoefficient(fixedWingCoefficient, stateOutput,
stateVariable, value)
fixedWingCoefficient = setCoefficient( ____, Name, Value)
```

Description

`fixedWingCoefficient = setCoefficient(fixedWingCoefficient, stateOutput, stateVariable, value)` sets the coefficient value `value` to the coefficient specified by `stateOutput` and `stateVariable` and returns the modified Aero.FixedWing.Coefficient object.

`fixedWingCoefficient = setCoefficient(____, Name, Value)` sets the coefficient value `value` to the coefficient specified by `stateOutput` and `stateVariable` and returns the modified object.

Input Arguments

fixedWingCoefficient — Aero.FixedWing.Coefficient object on which to set coefficient
scalar

Aero.FixedWing.Coefficient on which to set coefficient, specified as a scalar.

stateOutput — State output

6-by-1 vector

State output, specified as a 6-by-1 vector where each entry is a valid state output. For more information on state outputs, see Aero.FixedWing.Coefficient.

Data Types: char | string

stateVariable — State variable

vector

State variable, specified as a vector where each entry is a valid state variable. Valid state variables depend on the coefficients defined on the object. For more information on fixed-wing states, see Aero.FixedWing.State.

Data Types: char | string

value — State values

vector of cells

State values, specified as a vector of cells where each cell is a numeric constant or a `Simulink.LookupTable` object. For more information on coefficient values, see `Aero.FixedWing.Coefficient`.

Data Types: `double`

Name-Value Pair Arguments

Specify optional comma-separated pairs of `Name`, `Value` arguments. `Name` is the argument name and `Value` is the corresponding value. `Name` must appear inside quotes. You can specify several name and value pair arguments in any order as `Name1, Value1, ..., NameN, ValueN`.

Example: `'AddVariable', 'on'`

Component — Component name

`string`

Component name, specified as a string. Valid component names depend on the object properties and all subcomponents on the object. The default component name is the current object.

Data Types: `char` | `string`

AddVariable — Option to add state variable

`off` (default) | `on`

Add state variable if desired state variable is missing, specified as:

- `'on'` — Add a state variable.
- `'off'` — Do not add a state variable.

Data Types: `logical`

Output Arguments

fixedWingCoefficient — Modified fixed-wing coefficient object

`Aero.FixedWing.Coefficient`

Modified fixed-wing coefficient object on which coefficient is set, returned as `Aero.FixedWing.Coefficient`.

Examples

Set Coefficient for Aero.FixedWing Object

Set a coefficient on an `Aero.FixedWing` object.

```
C182 = astC182();  
C182 = setCoefficient(C182, "CD", "Alpha", {5})
```

```
C182 =
```

```
FixedWing with properties:
```

```
ReferenceArea: 174  
ReferenceSpan: 36
```

```

ReferenceLength: 4.9000
Coefficients: [1x1 Aero.FixedWing.Coefficient]
DegreesOfFreedom: "6DOF"
    Surfaces: [1x3 Aero.FixedWing.Surface]
    Thrusts: [1x1 Aero.FixedWing.Thrust]
AspectRatio: 7.4483
UnitSystem: "English (ft/s)"
AngleSystem: "Radians"
TemperatureSystem: "Fahrenheit"
Properties: [1x1 Aero.Aircraft.Properties]

```

Set Vector of Coefficients for Aero.FixedWing.Control Object

Set a vector of coefficient values on an `Aero.FixedWing.Control` object.

```

C182 = astC182();
C182 = setCoefficient(C182, ["CY"; "Cm"], ["Zero"; "Alpha"], {5; Simulink.LookupTable})

```

C182 =

FixedWing with properties:

```

ReferenceArea: 174
ReferenceSpan: 36
ReferenceLength: 4.9000
Coefficients: [1x1 Aero.FixedWing.Coefficient]
DegreesOfFreedom: "6DOF"
    Surfaces: [1x3 Aero.FixedWing.Surface]
    Thrusts: [1x1 Aero.FixedWing.Thrust]
AspectRatio: 7.4483
UnitSystem: "English (ft/s)"
AngleSystem: "Radians"
TemperatureSystem: "Fahrenheit"
Properties: [1x1 Aero.Aircraft.Properties]

```

Limitations

The vectors for the `stateOutput`, `stateVariable`, and `value` arguments must be the same length.

See Also

`Aero.FixedWing` | `getCoefficient` | `setCoefficient`

Introduced in R2021a

showAll

Package: satelliteScenario

Show all graphics in viewer

Syntax

```
showAll(viewer)
```

Description

`showAll(viewer)` shows all graphics in the specified satellite scenario viewer.

Input Arguments

viewer — Satellite scenario viewer

satelliteScenarioViewer object

Satellite scenario viewer, specified as a `satelliteScenarioViewer` object. `viewer` must be specified as a scalar `satelliteScenarioViewer` object.⁹

See Also

Objects

access | conicalSensor | groundStation | satelliteScenario |
satelliteScenarioViewer

Functions

camheading | camheight | campitch | campos | camroll | camtarget | hide | play | show

Topics

“Satellite Scenario Key Concepts” on page 2-61

Introduced in R2021a

9. Alignment of boundaries and region labels are a presentation of the feature provided by the data vendors and do not imply endorsement by MathWorks.

siderealTime

Greenwich mean and apparent sidereal times

Syntax

```
thGMST = siderealTime(utcJD)
thGMST = siderealTime(utcJD, dUT1, dAT)
[thGMST,thGAST] = siderealTime(utcJD,dUT1,dAT)
```

Description

`thGMST = siderealTime(utcJD)` calculates mean sidereal time at a specific Universal Coordinated Time (UTC), specified as a Julian date.

`thGMST = siderealTime(utcJD, dUT1, dAT)` calculates mean sidereal time at a specific Universal Coordinated Time (UTC) at a higher precision using Earth orientation parameters.

`[thGMST,thGAST] = siderealTime(utcJD,dUT1,dAT)` calculates mean and apparent sidereal times.

Note Apparent sidereal time calculation requires that you download ephemeris data using the Add-On Explorer. To start the Add-On Explorer, in the MATLAB Command Window, type `aeroDataPackage`. on the MATLAB desktop toolstrip, click the **Add-Ons** button.

Examples

Calculate Greenwich Sidereal Times for Particular Date

Calculate Greenwich sidereal times at 12:00 on January 4, 2019.

```
jd = juliandate([2019 1 4 12 0 0]);
[thGMST, thGAST] = siderealTime(jd);
```

Calculate Greenwich Sidereal Times for Whole Month

Calculate Greenwich sidereal times at 12:00 for the month of January, 2019:

```
dates = datetime([2019 1 4 12 0 0]);
dates = dates + days(1:30)';
jdJan = juliandate(dates);
[thGMST, thGAST] = siderealTime(jdJan);
```

Input Arguments

`utcJD` — UTC as Julian date

scalar

Universal Coordinated Time (UTC) as a Julian date, specified as a scalar.

Tip To calculate the Julian date for a particular date, use the `juliandate` function.

Data Types: double

dUT1 — Difference between CUT and UT1

0 (default) | scalar

Difference between the Coordinated Universal Time (UTC) and Universal Time (UT1), specified as a scalar, in seconds.

dAT — Difference between TAI and UTC

0 (default) | scalar

Difference between International Atomic Time (TAI) and Coordinated Universal Time (UTC), specified as a scalar, in seconds.

Output Arguments

thGMST — Greenwich mean sidereal time

scalar

Greenwich mean sidereal time, specified as a scalar, in seconds.

thGAST — Greenwich apparent sidereal time

scalar

Greenwich apparent sidereal time, specified as a scalar, in seconds.

Limitations

This function requires the Mapping Toolbox license.

References

[1] Vallado, D. A. *Fundamentals of Astrodynamics and Applications*. alg. 1 and eqs. 1-63. New York: McGraw-Hill, 1997.

See Also

CubeSat Vehicle | `dcmece2ecef` | `ecef2eci` | `eci2ecef`

Introduced in R2021a

setCoefficient

Class: Aero.FixedWing.Surface

Package: Aero

Set coefficient values for Aero.FixedWing.Surface object

Syntax

```
fixedWingSurface = setCoefficient(fixedWingSurface, stateOutput, stateVariable, value)
```

```
fixedWingSurface = setCoefficient( ____, Name, Value)
```

Description

`fixedWingSurface = setCoefficient(fixedWingSurface, stateOutput, stateVariable, value)` sets the coefficient value `value` to the coefficient specified by `stateOutput` and `stateVariable` and returns the modified surface object.

`fixedWingSurface = setCoefficient(____, Name, Value)` sets the coefficient value `value` to the coefficient specified by `stateOutput` and `stateVariable` and returns the modified surface object.

Input Arguments

fixedWingSurface — Aero.FixedWing.Surface object on which to set coefficient

scalar

Aero.FixedWing.Surface object on which to set coefficient, specified as a scalar.

stateOutput — State output

6-by-1 vector

State output, specified as a 6-by-1 vector where each entry is a valid state output. For more information on state outputs, see Aero.FixedWing.Coefficient.

Data Types: char | string

stateVariable — State variable

vector

State variable, specified as a vector where each entry is a valid state variable. Valid state variables depend on the coefficients defined on the object. For more information on fixed-wing states, see Aero.FixedWing.State.

Data Types: char | string

value — State values

vector of cells

State values, specified as a vector of cells where each cell is a numeric constant or a `Simulink.LookupTable` object. For more information on coefficient values, see `Aero.FixedWing.Coefficient`.

Data Types: `double`

Name-Value Pair Arguments

Specify optional comma-separated pairs of `Name`, `Value` arguments. `Name` is the argument name and `Value` is the corresponding value. `Name` must appear inside quotes. You can specify several name and value pair arguments in any order as `Name1, Value1, . . . , NameN, ValueN`.

Example: `'AddVariable', 'on'`

Component — Component name

`string`

Component name, specified as a string. Valid component names depend on the object properties and all subcomponents on the object. The default component name is the current object.

Data Types: `char` | `string`

AddVariable — Option to add state variable

`off` (default) | `on`

Option to add state variable if desired variable is missing, specified as:

- `'on'` — Add a state variable.
- `'off'` — Do not add a state variable.

Data Types: `logical`

Output Arguments

fixedWingSurface — Modified fixed-wing surface object

`Aero.FixedWing.Surface`

Modified fixed-wing surface object on which coefficient is set, returned as `Aero.FixedWing.Surface`.

See Also

`Aero.FixedWing` | `Aero.FixedWing.Coefficient` | `Aero.FixedWing.Surface` | `Aero.FixedWing.Thrust` | `getCoefficient`

Introduced in R2021a

setCoefficient

Class: Aero.FixedWing.Thrust

Package: Aero

Set coefficient values for Aero.FixedWing.Thrust object

Syntax

```
fixedWingThrust = setCoefficient(fixedWingThrust, stateOutput, stateVariable, value)
```

```
fixedWingThrust = setCoefficient( ____, Name, Value)
```

Description

`fixedWingThrust = setCoefficient(fixedWingThrust, stateOutput, stateVariable, value)` sets the coefficient value `value` to the coefficient specified by `stateOutput` and `stateVariable` and returns the modified thrust object.

`fixedWingThrust = setCoefficient(____, Name, Value)` sets the coefficient value `value` to the coefficient specified by `stateOutput` and `stateVariable` and returns the modified thrust object.

Input Arguments

fixedWingCoefficient — Aero.FixedWing.Thrust object on which to set coefficient

scalar

Aero.FixedWing.Thrust object on which to set coefficient, specified as a scalar.

stateOutput — State output

6-by-1 vector

State output, specified as a 6-by-1 vector where each entry is a valid state output. For more information on state outputs, see Aero.FixedWing.Coefficient.

Data Types: char | string

stateVariable — State variable

vector

State variable, specified as a vector where each entry is a valid state variable. Valid state variables depend on the coefficients defined on the object. For more information on fixed-wing states, see Aero.FixedWing.State.

Data Types: char | string

value — State values

vector of cells

State values, specified as a vector of cells where each cell is a numeric constant or a `Simulink.LookupTable` object. For more information on coefficient values, see `Aero.FixedWing.Coefficient`.

Data Types: `double`

Name-Value Pair Arguments

Specify optional comma-separated pairs of `Name`, `Value` arguments. `Name` is the argument name and `Value` is the corresponding value. `Name` must appear inside quotes. You can specify several name and value pair arguments in any order as `Name1, Value1, ..., NameN, ValueN`.

Example: `'AddVariable', 'on'`

Component — Component name

`string`

Component name, specified as a string. Valid component names depend on the object properties and all subcomponents on the object. The default component name is the current object.

Data Types: `char` | `string`

AddVariable — Option to add state variable

`off` (default) | `on`

Option to add state variable if desired state variable is missing, specified as:

- `'on'` — Add a state variable.
- `'off'` — Do not add a state variable.

Data Types: `logical`

Output Arguments

fixedWingThrust — Modified fixed-wing thrust object

`Aero.FixedWing.Thrust`

Modified fixed-wing thrust object on which coefficient is set, returned as `Aero.FixedWing.Thrust`.

See Also

`Aero.FixedWing.Thrust` | `getCoefficient`

Introduced in R2021a

setState

Class: Aero.FixedWing.State

Package: Aero

Set state value to Aero.FixedWing.State object

Syntax

```
state = setState(state, statename, value)
```

Description

`state = setState(state, statename, value)` sets the state `value` to a specified state name `value`.

Input Arguments

state — Aero.FixedWing.State object

scalar

Aero.FixedWing.State object, specified as a scalar.

statename — State names

vector

State names, specified in a vector. For more information on state names, see the Aero.FixedWing.State “Properties” on page 4-59.

Tip Each vector of `statename` and `value` must be the same length.

Data Types: char | string

value — State values

vector

State values, specified as a vector.

- If the states are all scalar constants, `value` is a numeric vector.
- If one of more states are not scalar constants, `value` is a cell vector.

Tip Each vector of `statename` and `value` must be the same length.

Output Arguments

state — Modified Aero.FixedWing.State object

vector

Modified input object with the modified states at the specified locations.

Examples

Set Pitch Angle of Cruise State

Set the pitch angle of a cruise state.

```
[C182, CruiseState] = astC182();
CruiseState = setState(CruiseState, "Alpha", 5)
```

CruiseState =

State with properties:

```

        Alpha: NaN
        Beta: NaN
        AlphaDot: 0
        BetaDot: 0
        Mass: 82.2981
        Inertia: [3×3 table]
        CenterOfGravity: [1.2936 0 0]
        CenterOfPressure: [1.2250 0 0]
        AltitudeMSL: 5000
        GroundHeight: 0
            XN: 0
            XE: 0
            XD: -5000
            U: 220.1000
            V: 0
            W: 0
        Phi: 0
        Theta: 0
        Psi: 0
            P: 0
            Q: 0
            R: 0
        Weight: 2.6500e+03
        AltitudeAGL: 5000
        Airspeed: NaN
        GroundSpeed: 220.1000
        MachNumber: NaN
        BodyVelocity: [NaN NaN NaN]
        GroundVelocity: [220.1000 0 0]
            Ur: NaN
            Vr: NaN
            Wr: NaN
        FlightPathAngle: 0
        CourseAngle: 0
        InertialToBodyMatrix: [3×3 double]
        BodyToInertialMatrix: [3×3 double]
        BodyToWindMatrix: [3×3 double]
        WindToBodyMatrix: [3×3 double]
        DynamicPressure: NaN
        Environment: [1×1 Aero.Aircraft.Environment]
        UnitSystem: "English (ft/s)"

```

```

    AngleSystem: "Radians"
  TemperatureSystem: "Fahrenheit"
    ControlStates: [1×4 Aero.Aircraft.ControlState]
  OutOfRangeAction: "Limit"
  DiagnosticAction: "Warning"
    Properties: [1×1 Aero.Aircraft.Properties]

```

Set U, V, and W Velocity Components

Set the U , V , and W velocity components of a cruise state.

```

[C182, CruiseState] = astC182();
CruiseState = setState(CruiseState, ["U", "V", "W"], [50, 1, 10])

```

CruiseState =

State with properties:

```

    Alpha: 0.1974
    Beta: 0.0196
  AlphaDot: 0
  BetaDot: 0
    Mass: 82.2981
    Inertia: [3×3 table]
  CenterOfGravity: [1.2936 0 0]
  CenterOfPressure: [1.2250 0 0]
    AltitudeMSL: 5000
  GroundHeight: 0
    XN: 0
    XE: 0
    XD: -5000
    U: 50
    V: 1
    W: 10
    Phi: 0
    Theta: 0
    Psi: 0
    P: 0
    Q: 0
    R: 0
    Weight: 2.6500e+03
  AltitudeAGL: 5000
    Airspeed: 51
  GroundSpeed: 51
    MachNumber: 0.0465
  BodyVelocity: [50 1 10]
  GroundVelocity: [50 1 10]
    Ur: 50
    Vr: 1
    Wr: 10
  FlightPathAngle: 0.1974
    CourseAngle: 0.0200
  InertialToBodyMatrix: [3×3 double]
  BodyToInertialMatrix: [3×3 double]
  BodyToWindMatrix: [3×3 double]
  WindToBodyMatrix: [3×3 double]

```

```
DynamicPressure: 2.6639
  Environment: [1x1 Aero.Aircraft.Environment]
  UnitSystem: "English (ft/s)"
  AngleSystem: "Radians"
TemperatureSystem: "Fahrenheit"
  ControlStates: [1x4 Aero.Aircraft.ControlState]
OutOfRangeAction: "Limit"
DiagnosticAction: "Warning"
  Properties: [1x1 Aero.Aircraft.Properties]
```

See Also

`Aero.FixedWing.State | getState | setupControlStates`

Introduced in R2021a

SetTimer (Aero.FlightGearAnimation)

Set name of timer for animation of FlightGear flight simulator

Syntax

```
SetTimer(h)
h.SetTimer
SetTimer(h, MyFGTimer)
h.SetTimer('MyFGTimer')
```

Description

`SetTimer(h)` and `h.SetTimer` set the name of the MATLAB timer for the animation of the FlightGear flight simulator. `SetTimer(h, MyFGTimer)` and `h.SetTimer('MyFGTimer')` set the name of the MATLAB timer for the animation of the FlightGear flight simulator and assign a custom name to the timer.

You can use this function to customize your FlightGear animation object. This customization allows you to simultaneously run multiple FlightGear objects if you want to use

- Multiple FlightGear sessions
- Different ports to connect to those sessions

Examples

Set the MATLAB timer for animation of the FlightGear animation object, `h`:

```
h = Aero.FlightGearAnimation
h.SetTimer
```

Set the MATLAB timer used for animation of the FlightGear animation object, `h`, and assign a custom name, `MyFGTimer`, to the timer:

```
h = Aero.FlightGearAnimation
h.SetTimer('MyFGTimer')
```

See Also

`ClearTimer`

Introduced in R2008b

setupControlStates

Class: Aero.FixedWing.State

Package: Aero

Set up control states for Aero.FixedWing.State object

Syntax

```
state = setupControlStates(aircraft, state)
```

Description

`state = setupControlStates(aircraft, state)` sets up initial control states for the Aero.FixedWing object.

Input Arguments

aircraft — Aero.FixedWing object

scalar

Aero.FixedWing object, specified as a scalar.

Data Types: double

state — Aero.FixedWing.State object

scalar

Aero.FixedWing.State object, specified as a scalar.

Output Arguments

state — Modified Aero.FixedWing.State object

scalar

Modified Aero.FixedWing.State object, returned as a scalar.

Data Types: double

Examples

Initialize Control and Command States

Initialize the control and command states on a cruise state.

```
[C182, CruiseState] = astC182();  
CruiseState = setupControlStates(CruiseState,C182)
```

```
CruiseState =
```

State with properties:

```

    Alpha: 0
    Beta: 0
    AlphaDot: 0
    BetaDot: 0
    Mass: 82.2981
    Inertia: [3×3 table]
    CenterOfGravity: [1.2936 0 0]
    CenterOfPressure: [1.2250 0 0]
    AltitudeMSL: 5000
    GroundHeight: 0
    XN: 0
    XE: 0
    XD: -5000
    U: 220.1000
    V: 0
    W: 0
    Phi: 0
    Theta: 0
    Psi: 0
    P: 0
    Q: 0
    R: 0
    Weight: 2.6500e+03
    AltitudeAGL: 5000
    Airspeed: 220.1000
    GroundSpeed: 220.1000
    MachNumber: 0.2006
    BodyVelocity: [220.1000 0 0]
    GroundVelocity: [220.1000 0 0]
    Ur: 220.1000
    Vr: 0
    Wr: 0
    FlightPathAngle: 0
    CourseAngle: 0
    InertialToBodyMatrix: [3×3 double]
    BodyToInertialMatrix: [3×3 double]
    BodyToWindMatrix: [3×3 double]
    WindToBodyMatrix: [3×3 double]
    DynamicPressure: 49.6149
    Environment: [1×1 Aero.Aircraft.Environment]
    UnitSystem: "English (ft/s)"
    AngleSystem: "Radians"
    TemperatureSystem: "Fahrenheit"
    ControlStates: [1×4 Aero.Aircraft.ControlState]
    OutOfRangeAction: "Limit"
    DiagnosticAction: "Warning"
    Properties: [1×1 Aero.Aircraft.Properties]

```

See Also

`Aero.FixedWing.State | getState | setState`

Introduced in R2021a

show

Package: satelliteScenario

Show object in satellite scenario viewer

Syntax

```
show(item)
show(item,v)
```

Description

`show(item)` shows the item on all open Satellite Scenario Viewers.

`show(item,v)` shows the graphic on the Satellite Scenario Viewer specified by `v`.

Examples

Add Satellites to Scenario Using Keplerian Elements

Create a satellite scenario with a start time of 02-June-2020 8:23:00 AM UTC, and the stop time set to one day later. Set the simulation sample time to 60 seconds.

```
startTime = datetime(2020,6,02,8,23,0);
stopTime = startTime + days(1);
sampleTime = 60;
sc = satelliteScenario(startTime,stopTime,sampleTime);
```

Add two satellites to the scenario using their Keplerian elements.

```
semiMajorAxis = [10000000; 15000000];
eccentricity = [0.01; 0.02];
inclination = [0; 10];
rightAscensionOfAscendingNode = [0; 15];
argumentOfPeriapsis = [0; 30];
trueAnomaly = [0; 20];

sat = satellite(sc, semiMajorAxis, eccentricity, inclination, ...
    rightAscensionOfAscendingNode, argumentOfPeriapsis, trueAnomaly)
```

```
sat =
    1x2 Satellite array with properties:
```

```
    Name
    ID
    ConicalSensors
    Gimbals
    Transmitters
    Receivers
    Accesses
    GroundTrack
```

```
Orbit
OrbitPropagator
MarkerColor
MarkerSize
ShowLabel
LabelFontSize
LabelFontColor
```

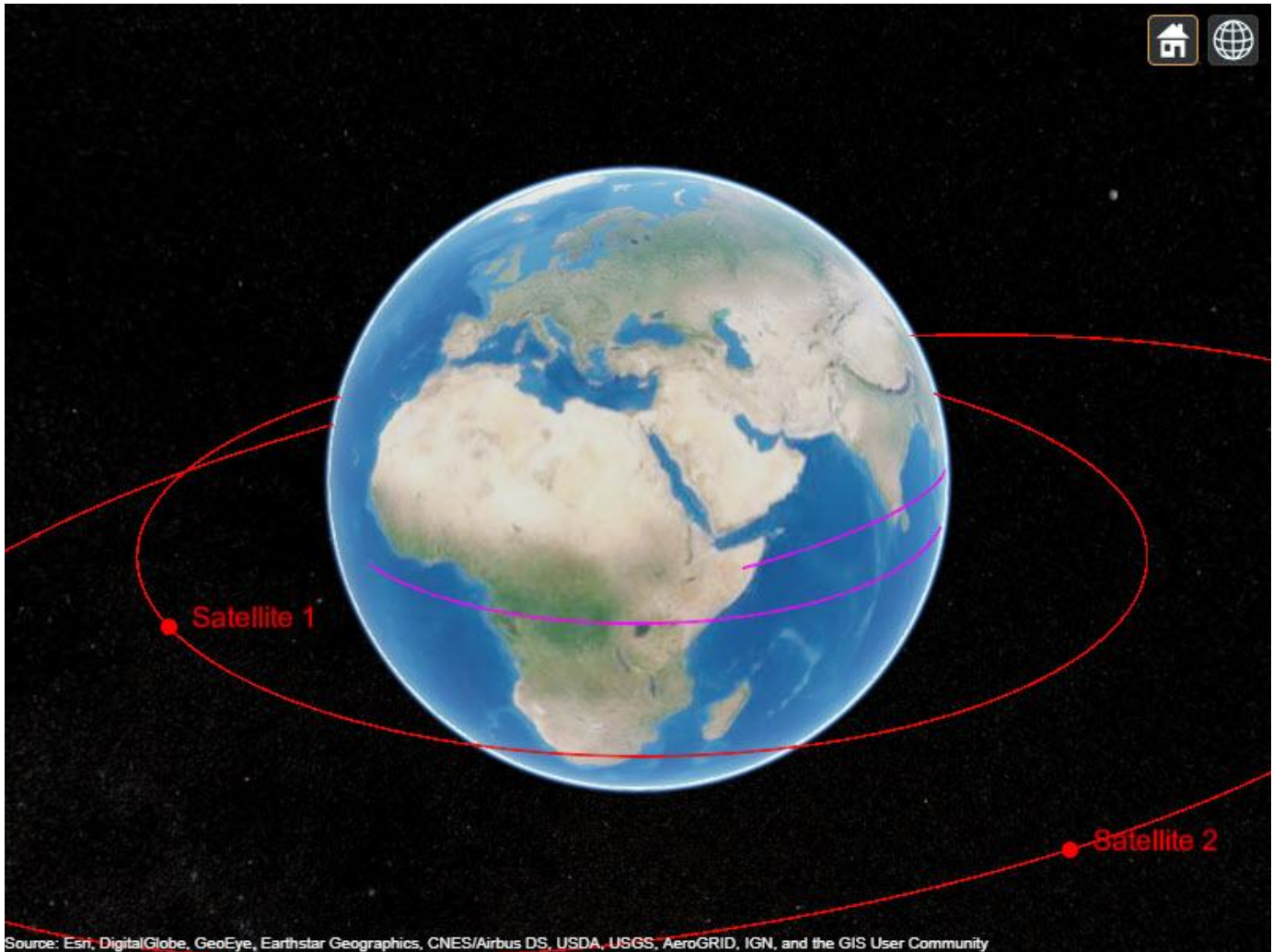
View the satellites in orbit and the ground tracks over one hour.

```
show(sat)
groundTrack(sat, 'LeadTime', 3600)

ans=1x2 object
  1x2 GroundTrack array with properties:

    LeadTime
    TrailTime
    LineWidth
    TrailLineColor
    LeadLineColor
    VisibilityMode
```

```
play(sc)
```



Input Arguments

item – Item

Satellite object | GroundStation object | ConicalSensor object | GroundTrack object | FieldofView object | Access object

Satellite, GroundStation, ConicalSensors, GroundTrack, FieldOfView, or Access object. These objects must belong to the same `satelliteScenario`, object.

Note If `item` is a satellite or a ground station, then the associated gimbals are also displayed on the viewer.

v – Satellite scenario viewer

`satelliteScenarioViewer` object

Satellite scenario viewer, specified as a `satelliteScenarioViewer` object.

See Also

Objects

satelliteScenario | satelliteScenarioViewer

Functions

access | conicalSensor | groundStation | hide | play

Topics

“Satellite Scenario Key Concepts” on page 2-61

Introduced in R2021a

show

Class: Aero.Animation

Package: Aero

Show animation object figure

Syntax

```
show(h)  
h.show
```

Description

`show(h)` and `h.show` create the figure graphics object for the animation object `h`. Use the `hide` function to close the figure.

Input Arguments

`h` Animation object.

Examples

Show the animation object, `h`.

```
h = Aero.Animation;  
idx1 = h.createBody('pa24-250_orange.ac', 'Ac3d');  
h.show;
```


states

Package: satelliteScenario

Position and velocity of satellite

Syntax

```
pos = states(sat)
[pos,velocity] = states(sat)
[___] = states(sat,timeIn)
[___] = states(____,'CoordinateFrame',C)
[pos,velocity,timeOut] = states(____)
```

Description

`pos = states(sat)` returns a 3-by- n matrix with the position history of the satellite `sat` in the Geocentric Celestial Reference Frame (GCRF), where n is the number of time samples in the satellite scenario simulation.

`[pos,velocity] = states(sat)` returns a 3-by- n matrix with the position and velocity history of satellite in GCRF.

`[___] = states(sat,timeIn)` also returns the outputs at the times specified by `timeIn`. Specify any output argument combinations from previous syntaxes.

`[___] = states(____,'CoordinateFrame',C)` returns the outputs in the coordinates specified by `C`.

`[pos,velocity,timeOut] = states(____)` returns the position and velocity history of the satellite and the corresponding time in Universal Time Coordinated (UTC).

Input Arguments

sat – Satellite

row vector of `Satellite` objects

Satellite, specified as a row vector of `Satellite` objects.

timeIn – Time at which output is calculated

scalar

Time at which the output is calculated, specified as a scalar. If you do not specify a time zone, then the time zone is assumed to be UTC.

C – Coordinate frame

'ecef' | 'inertial' | 'geographical'

Coordinate frame in which the outputs are returned, specified as 'ecef', 'inertial', or 'geographical'.

- The 'ecef' option returns the coordinates in the Earth Centered Earth Fixed (ECEF) frame. For more information on ECEF frames, see “Earth-Centered Earth-Fixed Coordinates” on page 2-62.
- The 'inertial' option returns the coordinates in the GCRF frame.
- The 'geographic' option returns the position as [*lat*; *lon*; *altitude*], where *lat* and *lon* are latitude and longitude in degrees, and *altitude* is the height above the wgs84 ellipsoid in meters. The velocity returned is ECEF, defined in the local North-East-Down (NED) frame.

Output Arguments

pos — Position history

scalar | vector | matrix | *N*-D array

Position history of the satellite, returned as a scalar, vector, matrix, or *N*-D array in the GCRF frame. Units are in meters.

velocity — Velocity history

scalar | vector | matrix | *N*-D array

Velocity history of the satellite, returned as a scalar, vector, matrix, or *N*-D array in the GCRF frame. Units are in meters/second.

timeOut — Time samples of position and velocity

scalar | vector | matrix | *N*-D array

Time samples of the position and velocity of the satellite, returned as a scalar, vector, matrix, or *N*-D array. If time histories of the position and velocity of the satellite are returned, `timeOut` is a row vector.

See Also

Objects

satelliteScenario | satelliteScenarioViewer

Functions

access | groundStation | hide | play | show

Topics

“Satellite Scenario Key Concepts” on page 2-61

Introduced in R2021a

staticStability

Class: Aero.FixedWing

Package: Aero

Calculate static stability of fixed-wing aircraft

Syntax

```
stability = staticStability(aircraft,state)
stability = staticStability( ____,Name,Value)
[stability,derivatives] = staticStability( ____ )
```

Description

`stability = staticStability(aircraft,state)` calculates the static stability `stability` of a fixed-wing aircraft `aircraft` at an `Aero.FixedWing.State` `state`. This method calculates static stability from changes in forces and moments due to perturbations of an aircraft state. By default, these states are airspeed, angle of attack, angle of side slip, and body roll rates. To change these states, see `criteriaTable`.

The `staticStability` method evaluates the changes in forces and moments after a perturbation as either greater than, equal to, or less than 0 using the matching entry in the criteria table.

- If the evaluation of a criterion is met, the aircraft is statically stable at that condition.
- If the evaluation of a criterion is not met, the aircraft is statically unstable at that condition.
- If the perturbation value is set to 0, the aircraft is statically neutral at that condition.

`stability = staticStability(____,Name,Value)` calculates the static stability result with the specified `Name,Value` arguments. Specify any of the input argument combinations in the previous syntaxes followed by `Name,Value` pairs as the last input arguments.

`[stability,derivatives] = staticStability(____)` returns the forces and moments derivatives table along with the static stability. Specify any of the input argument combinations in the previous syntaxes.

Input Arguments

aircraft — Aero.FixedWing object

scalar

Aero.FixedWing object, specified as a scalar.

Data Types: double

state — Aero.FixedWing.State object

scalar

Aero.FixedWing.State object, specified as a scalar.

Data Types: double

Name-Value Pair Arguments

Specify optional comma-separated pairs of `Name`, `Value` arguments. `Name` is the argument name and `Value` is the corresponding value. `Name` must appear inside quotes. You can specify several name and value pair arguments in any order as `Name1, Value1, ..., NameN, ValueN`.

Example: `'RelativePerturbation', '1e-5'`

CriteriaTable — Static stability test criteria

6-by-8 table (default) | 6-by-*N* table

Static stability test criteria, specified as a 6-by-*N* table, where *N* is number of variables.

- If the value being evaluated is 0, it is neutral.
- If the value being evaluated does not meet the criteria, it is unstable.
- If the criterion is an empty string or is missing, then the stability result is an empty string.

The criteria table has these requirements:

- Each entry in the criteria table must be '<', '>', '', or missing.
- The table must have six rows: 'FX', 'FY', 'FZ', 'L', 'M', and 'N'.
- *N* number of variables for columns.

By default, this table appears as:

	U	V	W	Alpha	Beta	P	Q	R
FX	'<'	''	''	''	''	''	''	''
FY	''	'<'	''	''	''	''	''	''
FZ	''	''	'<'	''	''	''	''	''
L	''	''	''	''	''	'<'	'<'	''
M	'>'	''	''	'<'	''	''	'<'	''
N	''	''	''	''	'>'	''	''	'<'

Data Types: string

RelativePerturbation — Relative perturbation

1e-5 (default) | scalar numeric

Relative perturbation of the system, specified as a scalar numeric. This perturbation takes the form of:

Perturbation Type	Definition
System State perturbation	<code>statePert = RelativePerturbation + 1e-3*RelativePerturbation* baseValue </code>
System input perturbation	<code>ctrlPert = RelativePerturbation + 1e-3*RelativePerturbation* baseValue </code>

To calculate the Jacobian of the system, `linearize` uses the result of these equations in conjunction with the 'DifferentialMethod' property.

Example: `'RelativePerturbation', 1e-5`

Data Types: double

DifferentialMethod — Direction while perturbing model

'Forward' (default) | 'Backward' | 'Central'

Direction while perturbing, specified as 'Forward', 'Backward', or 'Central'.

Direction	Description
'Forward'	Forward difference method that adds statePert and ctrlPert to the base states and inputs, respectively.
'Backward'	Backward difference method that adds statePert and ctrlPert to the base states and inputs, respectively.
'Central'	Central difference method that adds and subtracts statePert and ctrlPert to and from the base states and inputs, respectively.

Example: 'DifferentialMethod', 'Backward'

Data Types: char | string

Output Arguments

stability — Stability of fixed-wing aircraft

6-by-*N* table

Stability of fixed-wing aircraft, returned as a 6-by-*N* table.

derivatives — Forces and moments derivatives

6-by-*N* table

Forces and moments derivatives, returned as a 6-by-*N* table.

Examples

Calculate Static Stability of Cessna C182

Calculate the static stability of a Cessna C182.

```
[C182, CruiseState] = astC182();
stability = staticStability(C182, CruiseState)
```

stability =

6×8 table

	U	V	W	Alpha	Beta	P	Q	
FX	"Stable"	" "	" "	" "	" "	" "	" "	" "
FY	" "	"Stable"	" "	" "	" "	" "	" "	" "

FZ	""	""	"Stable"	""	""	""	""	""
L	""	""	""	""	"Stable"	"Stable"	""	""
M	"Stable"	""	""	"Stable"	""	""	"Stable"	""
N	""	""	""	""	"Stable"	""	""	""

Calculate Static Stability of Cessna C182 with Custom Criteria Table

Calculate the static stability of a Cessna C182 with a custom criteria table.

```
[C182, CruiseState] = astC182();
CT = C182.criteriaTable()
CT{"FX", "U"} = ">"
stability = staticStability(C182, CruiseState, "CriteriaTable", CT)
```

CT =

6x8 table

	U	V	W	Alpha	Beta	P	Q	R
FX	"<"	""	""	""	""	""	""	""
FY	""	"<"	""	""	""	""	""	""
FZ	""	""	"<"	""	""	""	""	""
L	""	""	""	""	"<"	"<"	""	""
M	">"	""	""	"<"	""	""	"<"	""
N	""	""	""	""	">"	""	""	"<"

CT =

6x8 table

	U	V	W	Alpha	Beta	P	Q	R
FX	">"	""	""	""	""	""	""	""
FY	""	"<"	""	""	""	""	""	""
FZ	""	""	"<"	""	""	""	""	""
L	""	""	""	""	"<"	"<"	""	""
M	">"	""	""	"<"	""	""	"<"	""
N	""	""	""	""	">"	""	""	"<"

stability =

6x8 table

	U	V	W	Alpha	Beta	P	Q
FX	"Unstable"	""	""	""	""	""	""
FY	""	"Stable"	""	""	""	""	""
FZ	""	""	"Stable"	""	""	""	""
L	""	""	""	""	"Stable"	"Stable"	""

```

M  "Stable"  ""      ""      "Stable"  ""      ""      "Stable"
N  ""        ""      ""      ""        "Stable"  ""      ""

```

Calculate Static Stability of Cessna C182 with Central Differential Method

Calculate the static stability of a Cessna C182 using the central differential method.

```

[C182, CruiseState] = astC182();
stability = staticStability(C182, CruiseState, "DifferentialMethod", "Central")

```

stability =

6×8 table

	U	V	W	Alpha	Beta	P	Q	
FX	"Stable"	""	""	""	""	""	""	""
FY	""	"Stable"	""	""	""	""	""	""
FZ	""	""	"Stable"	""	""	""	""	""
L	""	""	""	""	"Stable"	"Stable"	""	""
M	"Stable"	""	""	"Stable"	""	""	"Stable"	""
N	""	""	""	""	"Stable"	""	""	""

Calculate Static Stability and Derivatives of Cessna C182

Calculate the static stability and derivatives of a Cessna C182.

```

[C182, CruiseState] = astC182();
[stability,derivatives] = staticStability(C182, CruiseState)

```

stability =

6×8 table

	U	V	W	Alpha	Beta	P	Q	R
FX	"Stable"	""	""	""	""	""	""	""
FY	""	"Stable"	""	""	""	""	""	""
FZ	""	""	"Stable"	""	""	""	""	""
L	""	""	""	""	"Stable"	"Stable"	""	""
M	"Stable"	""	""	"Stable"	""	""	"Stable"	""
N	""	""	""	""	"Stable"	""	""	"Stable"

derivatives =

6×8 table

	U	V	W	Alpha	Beta	P	Q	R
FX	-2.118	-5.4001e-08	7.2955	1606.1	-0.0023309	0	0	0
FY	0	-15.415	0	0	-3392.8	-647.47	0	1847.5
FZ	-24.083	-5.9117e-07	-174.03	-38305	-0.026503	0	-33669	0
L	0	-130.33	0	0	-28686	-1.5042e+05	0	24801
M	17.028	4.5475e-07	-105.88	-23303	0.018739	0	-5.2223e+05	0
N	0	83.944	0	0	18476	-8595.5	0	-29248

See Also

[Aero.FixedWing](#) | [criteriaTable](#) | [forcesAndMoments](#) | [linearize](#)

Introduced in R2021a

tdbjuliandate

Convert from Barycentric Dynamical Time Estimate to Julian date

Syntax

```
jdtdb = tdbjuliandate(terrestrial_time)
[jdtdb,tttdb] = tdbjuliandate(terrestrial_time)
```

Description

`jdtdb = tdbjuliandate(terrestrial_time)` returns an estimate of the Julian date for Barycentric Dynamical Time (TDB). These estimations are valid for the years 1980 to 2050.

`[jdtdb,tttdb] = tdbjuliandate(terrestrial_time)` additionally returns an array of Julian dates for the Barycentric Dynamical Time (TDB) based on the Terrestrial Time (TT).

Examples

Estimate Julian Date for Barycentric Dynamical Time

Estimate the Julian date for the Barycentric Dynamical Time for the Terrestrial Time 2014/10/15 16:22:31.

```
jdtdb = tdbjuliandate([2014,10,15,16,22,31])
```

```
jdtdb =
    2.4569e+06
```

Estimate Julian Dates for the Barycentric Dynamical Time and TT-TDB

Estimate the Julian dates for the Barycentric Dynamical Time and TT-TDB in seconds for the terrestrial time 2014/10/15 16:22:31 and 2010/7/22 1:57:17.

```
[jdtdb,tttdb] = tdbjuliandate([2014,10,15,16,22,31;2010,7,22,1,57,17])
```

```
JDTDB =
    1.0e+06 *
    2.4569
    2.4554
```

```
TTTTDB =
```

```
0.0016  
0.0005
```

Input Arguments

terrestrial_time — Terrestrial Time

1-by-6 array | M -by-6 array

Terrestrial Time (TT) in year, month, day, hour, minutes, and seconds for which the function calculates the Julian date for Barycentric Dynamical Time. M is the number of Julian dates, one for each TT date. Specify values for year, month, day, hour, and minutes as whole numbers.

Output Arguments

jdtodb — Julian date

M -by-1 array

Julian date for the Barycentric Dynamical Time, returned as an M -by-1 array. M is the number of rows, one for each Terrestrial Time input.

tttdb — Difference in seconds

M -by-1 array

Difference in seconds between Terrestrial Time and Barycentric Dynamical Time (TT-TDB), returned as an M -by-1 array. M is the number of rows, one for each Terrestrial Time input.

Limitations

Fundamentals of Astrodynamics and Applications[1] indicates an accuracy of 50 microseconds, which this function cannot achieve due to numerical issues with the values involved.

References

[1] Vallado, D. A., *Fundamentals of Astrodynamics and Applications*, New York: McGraw-Hill, 1997.

See Also

`dcmece2ecef` | `ecef2lla` | `geoc2geod` | `geod2geoc` | `lla2ecef` | `lla2eci`

Introduced in R2015a

TurnCoordinator Properties

Control turn coordinator appearance and behavior

Description

Turn coordinators are components that represent a turn coordinator. Properties control the appearance and behavior of a turn coordinator. Use dot notation to refer to a particular object and property:

```
f = uifigure;
turn = uiaeroturn(f);
turn.Turn = 100;
```

The turn coordinator displays measurements on a turn coordinator and inclinometer. These measurements help determine if the turn is coordinated, slipped, or skidded. The turn is a coordinated turn that combines the rolling and yawing of a turn. The turn indicator signal turns the airplane in the gauge, in degrees. The inclinometer turns the ball in the gauge, in degrees. Together, these signals show the slip and skid of an airplane as it turns. Tilt angle values are limited to ± 20 degrees. Slip values are limited to ± 15 degrees.

Properties

Turn Coordinator

Slip — Slip

0 (default) | finite, real, and scalar numeric

Slip value, specified as any finite and scalar numeric. The slip value controls the direction of the inclinometer ball. A negative value moves the ball to the right, a positive value moves the ball to the left, in degrees. This value cannot exceed ± 15 degrees. If it exceed 15 degrees, the gauge stays fixed at the minimum or maximum value.

Example: 10

Dependencies

Specifying this value changes the second element of the `Value` vector. Conversely, changing the second element of the `Value` vector changes the `Slip` value.

Data Types: `double`

Turn — Turn

0 (default) | finite, real, and scalar numeric

Turn rate value, specified as any finite and scalar numeric, in degrees. Input the turn rate value as the degrees of tilt of the aircraft symbol in the gauge. The standard rate turn marks are at angles of ± 15 degrees. Tilt angle values are limited to ± 20 degrees.

Example: 10

Dependencies

Specifying this value changes the first element of the `Value` vector. Conversely, changing the first element of the `Value` vector changes the `Turn` value.

Data Types: `double`

Value — Turn and slip

[0 0] (default) | two-element vector of finite, real, and scalar numerics

Turn and slip values, specified as a vector (`[Turn Slip]`).

- The turn rate value indicates the aircraft heading rate of change by the degrees of tilt of the aircraft symbol.
- The slip value controls the direction of the inclinometer ball. A negative value moves the ball to the right, and a positive value moves the ball to the left.

Example: `[15 0]` indicates a coordinated, standard rate turn.

Dependencies

- Specifying the `Turn` value changes the first element of the `Value` vector. Conversely, changing the first element of the `Value` vector changes the `Turn` value.
- Specifying the `Slip` value changes the second element of the `Value` vector. Conversely, changing the second element of the `Value` vector changes the `Slip` value.

Data Types: `double`

Interactivity**Visible — Visibility of turn coordinator**

'on' (default) | on/off logical value

Visibility of the turn coordinator, specified as 'on' or 'off', or as numeric or logical 1 (`true`) or 0 (`false`). A value of 'on' is equivalent to `true`, and 'off' is equivalent to `false`. Thus, you can use the value of this property as a logical value. The value is stored as an on/off logical value of type `matlab.lang.OnOffSwitchState`. The `Visible` property determines whether the turn coordinator is displayed on the screen. If the `Visible` property is set to 'off', then the entire turn coordinator is hidden, but you can still specify and access its properties.

ContextMenu — Context menu

empty `GraphicsPlaceholder` array (default) | `ContextMenu` object

Context menu, specified as a `ContextMenu` object created using the `uicontextmenu` function. Use this property to display a context menu when you right-click on a component.

Enable — Operational state of turn coordinator

'on' (default) | on/off logical value

Operational state of turn coordinator, specified as 'on' or 'off', or as numeric or logical 1 (`true`) or 0 (`false`). A value of 'on' is equivalent to `true`, and 'off' is equivalent to `false`. Thus, you can use the value of this property as a logical value. The value is stored as an on/off logical value of type `matlab.lang.OnOffSwitchState`.

- If you set this property to 'on', then the appearance of the turn coordinator indicates that the turn coordinator is operational.

- If you set this property to 'off', then the appearance of the turn coordinator appears dimmed, indicating that the turn coordinator is not operational.

Position

Position — Location and size of turn coordinator

[100 100 120 120] (default) | [left bottom width height]

Location and size of the turn coordinator relative to the parent container, specified as the vector [left bottom width height]. This table describes each element in the vector.

Element	Description
left	Distance from the inner left edge of the parent container to the outer left edge of an imaginary box surrounding the turn coordinator
bottom	Distance from the inner bottom edge of the parent container to the outer bottom edge of an imaginary box surrounding the turn coordinator
width	Distance between the right and left outer edges of the turn coordinator
height	Distance between the top and bottom outer edges of the turn coordinator

All measurements are in pixel units.

The **Position** values are relative to the drawable area of the parent container. The drawable area is the area inside the borders of the container and does not include the area occupied by decorations such as a menu bar or title.

Example: [200 120 120 120]

InnerPosition — Inner location and size of turn coordinator

[100 100 120 120] (default) | [left bottom width height]

Inner location and size of the turn coordinator, specified as [left bottom width height]. Position values are relative to the parent container. All measurements are in pixel units. This property value is identical to the **Position** property.

OuterPosition — Outer location and size of turn coordinator

[100 100 120 120]] (default) | [left bottom width height]

This property is read-only.

Outer location and size of the turn coordinator returned as [left bottom width height]. Position values are relative to the parent container. All measurements are in pixel units. This property value is identical to the **Position** property.

Layout — Layout options

empty `LayoutOptions` array (default) | `GridLayoutOptions` object

Layout options, specified as a `GridLayoutOptions` object. This property specifies options for components that are children of grid layout containers. If the component is not a child of a grid layout container (for example, it is a child of a figure or panel), then this property is empty and has no effect.

However, if the component is a child of a grid layout container, you can place the component in the desired row and column of the grid by setting the `Row` and `Column` properties on the `GridLayoutOptions` object.

For example, this code places an turn coordinator in the third row and second column of its parent grid.

```
g = uigridlayout([4 3]);  
gauge = uiaereturn(g);  
gauge.Layout.Row = 3;  
gauge.Layout.Column = 2;
```

To make the turn coordinator span multiple rows or columns, specify the `Row` or `Column` property as a two-element vector. For example, this turn coordinator spans columns 2 through 3:

```
gauge.Layout.Column = [2 3];
```

Callbacks

CreateFcn — Creation function

' ' (default) | function handle | cell array | character vector

Object creation function, specified as one of these values:

- Function handle.
- Cell array in which the first element is a function handle. Subsequent elements in the cell array are the arguments to pass to the callback function.
- Character vector containing a valid MATLAB expression (not recommended). MATLAB evaluates this expression in the base workspace.

For more information about specifying a callback as a function handle, cell array, or character vector, see “Write Callbacks in App Designer”.

This property specifies a callback function to execute when MATLAB creates the object. MATLAB initializes all property values before executing the `CreateFcn` callback. If you do not specify the `CreateFcn` property, then MATLAB executes a default creation function.

Setting the `CreateFcn` property on an existing component has no effect.

If you specify this property as a function handle or cell array, you can access the object that is being created using the first argument of the callback function. Otherwise, use the `gcbo` function to access the object.

DeleteFcn — Deletion function

' ' (default) | function handle | cell array | character vector

Object deletion function, specified as one of these values:

- Function handle.
- Cell array in which the first element is a function handle. Subsequent elements in the cell array are the arguments to pass to the callback function.
- Character vector containing a valid MATLAB expression (not recommended). MATLAB evaluates this expression in the base workspace.

For more information about specifying a callback as a function handle, cell array, or character vector, see “Write Callbacks in App Designer”.

This property specifies a callback function to execute when MATLAB deletes the object. MATLAB executes the `DeleteFcn` callback before destroying the properties of the object. If you do not specify the `DeleteFcn` property, then MATLAB executes a default deletion function.

If you specify this property as a function handle or cell array, you can access the object that is being deleted using the first argument of the callback function. Otherwise, use the `gcbo` function to access the object.

Callback Execution Control

Interruptible — Callback interruption

'on' (default) | on/off logical value

Callback interruption, specified as 'on' or 'off', or as numeric or logical 1 (true) or 0 (false). A value of 'on' is equivalent to true, and 'off' is equivalent to false. Thus, you can use the value of this property as a logical value. The value is stored as an on/off logical value of type `matlab.lang.OnOffSwitchState`.

This property determines if a running callback can be interrupted. There are two callback states to consider:

- The running callback is the currently executing callback.
- The interrupting callback is a callback that tries to interrupt the running callback.

Whenever MATLAB invokes a callback, that callback attempts to interrupt the running callback (if one exists). The `Interruptible` property of the object owning the running callback determines if interruption is allowed.

- A value of 'on' allows other callbacks to interrupt the object's callbacks. The interruption occurs at the next point where MATLAB processes the queue, such as when there is a `drawnow`, `figure`, `uifigure`, `getframe`, `waitfor`, or `pause` command.
 - If the running callback contains one of those commands, then MATLAB stops the execution of the callback at that point and executes the interrupting callback. MATLAB resumes executing the running callback when the interrupting callback completes.
 - If the running callback does not contain one of those commands, then MATLAB finishes executing the callback without interruption.
- A value of 'off' blocks all interruption attempts. The `BusyAction` property of the object owning the interrupting callback determines if the interrupting callback is discarded or put into a queue.

Note Callback interruption and execution behave differently in these situations:

- If the interrupting callback is a `DeleteFcn`, `CloseRequestFcn` or `SizeChangedFcn` callback, then the interruption occurs regardless of the `Interruptible` property value.
- If the running callback is currently executing the `waitfor` function, then the interruption occurs regardless of the `Interruptible` property value.
- Timer objects execute according to schedule regardless of the `Interruptible` property value.

When an interruption occurs, MATLAB does not save the state of properties or the display. For example, the object returned by the `gca` or `gcf` command might change when another callback executes.

BusyAction — Callback queuing

'queue' (default) | 'cancel'

Callback queuing, specified as 'queue' or 'cancel'. The `BusyAction` property determines how MATLAB handles the execution of interrupting callbacks. There are two callback states to consider:

- The running callback is the currently executing callback.
- The interrupting callback is a callback that tries to interrupt the running callback.

Whenever MATLAB invokes a callback, that callback attempts to interrupt a running callback. The `Interruptible` property of the object owning the running callback determines if interruption is permitted. If interruption is not permitted, then the `BusyAction` property of the object owning the interrupting callback determines if it is discarded or put in the queue. These are possible values of the `BusyAction` property:

- 'queue' — Puts the interrupting callback in a queue to be processed after the running callback finishes execution.
- 'cancel' — Does not execute the interrupting callback.

BeingDeleted — Deletion status

on/off logical value

This property is read-only.

Deletion status, returned as an on/off logical value of type `matlab.lang.OnOffSwitchState`.

MATLAB sets the `BeingDeleted` property to 'on' when the `DeleteFcn` callback begins execution. The `BeingDeleted` property remains set to 'on' until the component object no longer exists.

Check the value of the `BeingDeleted` property to verify that the object is not about to be deleted before querying or modifying it.

Parent/Child

Parent — Parent container

Figure object (default) | Panel object | Tab object | ButtonGroup object | GridLayout object

Parent container, specified as a `Figure` object created using the `uifigure` function, or one of its child containers: `Tab`, `Panel`, `ButtonGroup`, or `GridLayout`. If no container is specified, MATLAB calls the `uifigure` function to create a new `Figure` object that serves as the parent container.

HandleVisibility — Visibility of object handle

'on' (default) | 'callback' | 'off'

Visibility of the object handle, specified as 'on', 'callback', or 'off'.

This property controls the visibility of the object in its parent's list of children. When an object is not visible in its parent's list of children, it is not returned by functions that obtain objects by searching the object hierarchy or querying properties. These functions include `get`, `findobj`, `clf`, and `close`.

Objects are valid even if they are not visible. If you can access an object, you can set and get its properties, and pass it to any function that operates on objects.

HandleVisibility Value	Description
'on'	The object is always visible.
'callback'	The object is visible from within callbacks or functions invoked by callbacks, but not from within functions invoked from the command line. This option blocks access to the object at the command-line, but allows callback functions to access it.
'off'	The object is invisible at all times. This option is useful for preventing unintended changes to the UI by another function. Set the <code>HandleVisibility</code> to 'off' to temporarily hide the object during the execution of that function.

Identifiers

Type — Type of graphics object

'uiaereturn'

This property is read-only.

Type of graphics object, returned as 'uiaereturn'.

Tag — Object identifier

' ' (default) | character vector | string scalar

Object identifier, specified as a character vector or string scalar. You can specify a unique `Tag` value to serve as an identifier for an object. When you need access to the object elsewhere in your code, you can use the `findobj` function to search for the object based on the `Tag` value.

UserData — User data

[] (default) | array

User data, specified as any MATLAB array. For example, you can specify a scalar, vector, matrix, cell array, character array, table, or structure. Use this property to store arbitrary data on an object.

If you are working in App Designer, create public or private properties in the app to share data instead of using the `UserData` property. For more information, see “Share Data Within App Designer Apps”.

See Also

uiaereturn

Topics

“Create and Configure Flight Instrument Component and an Animation Object” on page 2-49

“Display Flight Trajectory Data Using Flight Instruments and Flight Animation” on page 5-111

Introduced in R2018b

uiaeroairspeed

Package: Aero.ui.control

Create airspeed indicator component

Syntax

```
airspeed = uiaeroairspeed
airspeed = uiaeroairspeed(parent)
airspeed = uiaeroairspeed( ___,Name,Value)
```

Description

`airspeed = uiaeroairspeed` creates an airspeed indicator in a new figure. MATLAB calls the `uifigure` function to create the figure.

The airspeed indicator displays measurements for aircraft airspeed in knots.

By default, minor ticks represent 10-knot increments and major ticks represent 40-knot increments. The parameters **Minimum** and **Maximum** determine the minimum and maximum values on the gauge. The number and distribution of ticks is fixed, which means that the first and last tick display the minimum and maximum values. The ticks in between distribute evenly between the minimum and maximum values. For major ticks, the distribution of ticks is $(\mathbf{Maximum}-\mathbf{Minimum})/9$. For minor ticks, the distribution of ticks is $(\mathbf{Maximum}-\mathbf{Minimum})/36$.

The airspeed indicator has scale color bars that allow for overlapping for the first bar, displayed at a different radius. This different radius lets the gauge represent V_{FE} (maximum speed with flap extended) and V_{SO} (stall speed with flap extended) accurately for aircraft airspeed and stall speed.

If the value of the input is under **Minimum**, the needle displays 5 degrees under the **Minimum** value. If the value exceeds the **Maximum** value, the needle displays 5 degrees over the maximum tick.

Note Use this function only with figures created using the `uifigure` function. Apps created using GUIDE or the `figure` function do not support flight instrument components.

`airspeed = uiaeroairspeed(parent)` specifies the object in which to create the airspeed indicator.

`airspeed = uiaeroairspeed(___,Name,Value)` specifies airspeed indicator properties using one or more `Name,Value` pair arguments. Use this option with any of the input argument combinations in the previous syntaxes.

Examples

Create Airspeed Indicator Component

Create an airspeed indicator component named `airspeed`. By default, the function creates a `uifigure` object for the indicator object.

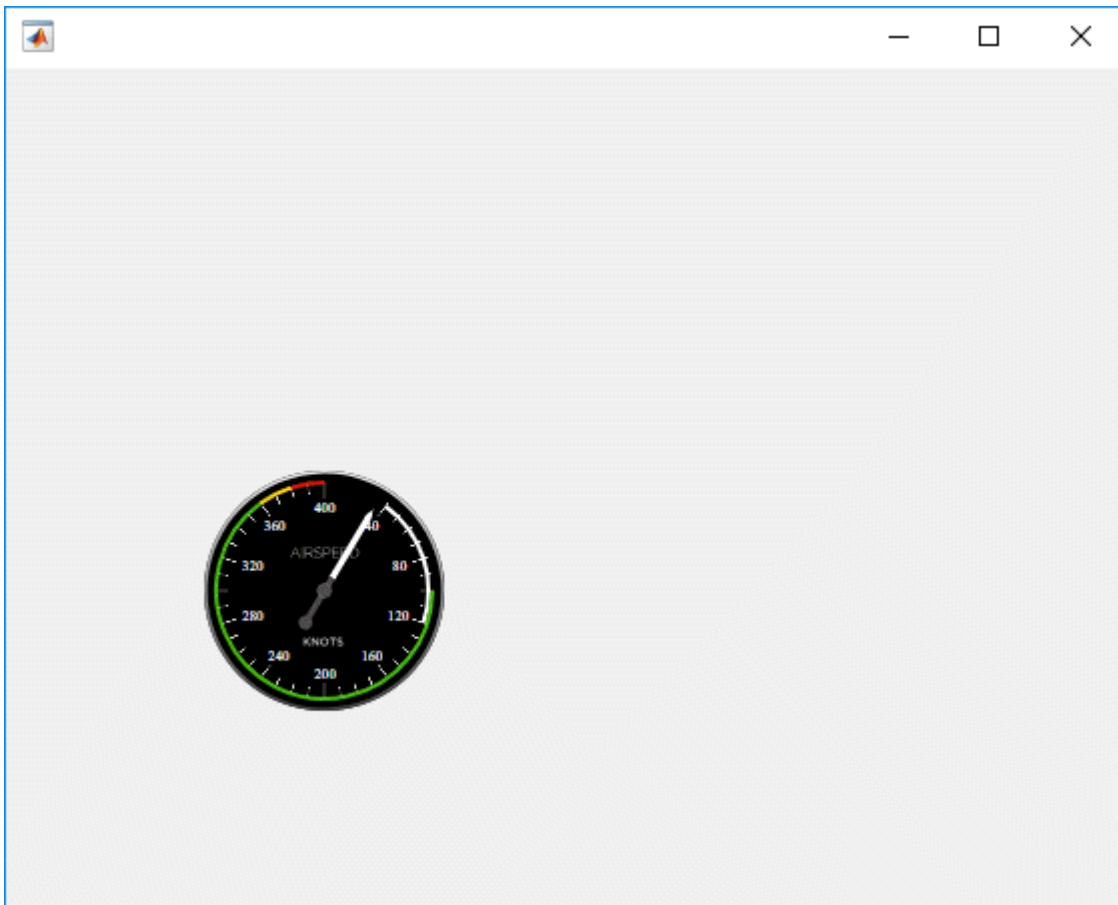
```
airspeed = uiaeroairspeed
```

```
airspeed =
```

```
AirspeedIndicator (0) with properties:
```

```
    Airspeed: 0  
   ScaleColors: [4x3 double]  
ScaleColorLimits: [4x2 double]  
        Limits: [40 400]  
   Position: [100 100 120 120]
```

```
Show all properties
```



Create Figure Window and Airspeed Indicator Component

Create a figure window to contain the airspeed indicator component, then create an airspeed indicator component named `airspeed`.

```
f = uifigure;
air speed = uiaeroair speed(f)

air speed =

    Air speedIndicator (0) with properties:

        Air speed: 0
        ScaleColors: [4x3 double]
        ScaleColorLimits: [4x2 double]
        Limits: [40 400]
        Position: [100 100 120 120]

    Show all properties
```

Input Arguments

parent — Parent container

Figure object (default) | Panel object | Tab object | ButtonGroup object | GridLayout object

Parent container, specified as a **Figure** object created using the **uifigure** function, or one of its child containers: **Tab**, **Panel**, **ButtonGroup**, or **GridLayout**. If you do not specify a parent container, MATLAB calls the **uifigure** function to create a new **Figure** object that serves as the parent container.

Name-Value Pair Arguments

Specify optional comma-separated pairs of **Name**, **Value** arguments. **Name** is the argument name and **Value** is the corresponding value. **Name** must appear inside quotes. You can specify several name and value pair arguments in any order as **Name1**, **Value1**, ..., **NameN**, **ValueN**.

For a full list of air speed indicator properties and descriptions for each type, see **Air speedIndicator Properties**.

Output Arguments

air speed — Air speed indicator component

object

Air speed indicator component, returned as an object.

See Also

Air speedIndicator Properties

Topics

“Create and Configure Flight Instrument Component and an Animation Object” on page 2-49

“Display Flight Trajectory Data Using Flight Instruments and Flight Animation” on page 5-111

Introduced in R2018b

uiaeroaltimeter

Package: Aero.ui.control

Create altimeter component

Syntax

```
altimeter = uiaeroaltimeter
altimeter = uiaeroaltimeter(parent)
altimeter = uiaeroaltimeter( ___,Name,Value)
```

Description

`altimeter = uiaeroaltimeter` creates an altimeter in a new figure. MATLAB calls the `uifigure` function to create the figure.

The altimeter displays the altitude above sea level in feet, also known as the pressure altitude. It displays the altitude value with needles on a gauge and a numeric indicator.

- The gauge has 10 major ticks. Within each major tick are five minor ticks. This gauge has three needles. Using the needles, the altimeter can display accurately only altitudes between 0 and 100,000 feet.
 - For the longest needle, an increment of a small tick represents 20 feet and a major tick represents 100 feet.
 - For the second longest needle, a minor tick represents 200 feet and a major tick represents 1,000 feet.
 - For the shortest needle a minor tick represents 2,000 feet and a major tick represents 10,000 feet.
- For the numeric display, the gauge shows values as numeric characters between 0 and 9,999 feet. When the numeric display value reaches 10,000 feet, the gauge displays the value as the remaining values below 10,000 feet. For example, 12,345 feet displays as 2,345 feet. When a value is less than 0 (below sea level), the gauge displays 0. The needles show the appropriate value except for when the value is below sea level or over 100,000 feet. Below sea level, the needles set to 0, over 100,000, the needles stay set at 100,000.

Note Use this function only with figures created using the `uifigure` function. Apps created using GUIDE or the `figure` function do not support flight instrument components.

`altimeter = uiaeroaltimeter(parent)` specifies the object in which to create the altimeter.

`altimeter = uiaeroaltimeter(___,Name,Value)` specifies altimeter properties using one or more `Name,Value` pair arguments. Use this option with any of the input argument combinations in the previous syntaxes.

Examples

Create Altimeter Component

Create an altimeter component named `altimeter`. By default, the function creates a `uifigure` object for the indicator object.

```
altimeter = uiaeroaltimeter
```

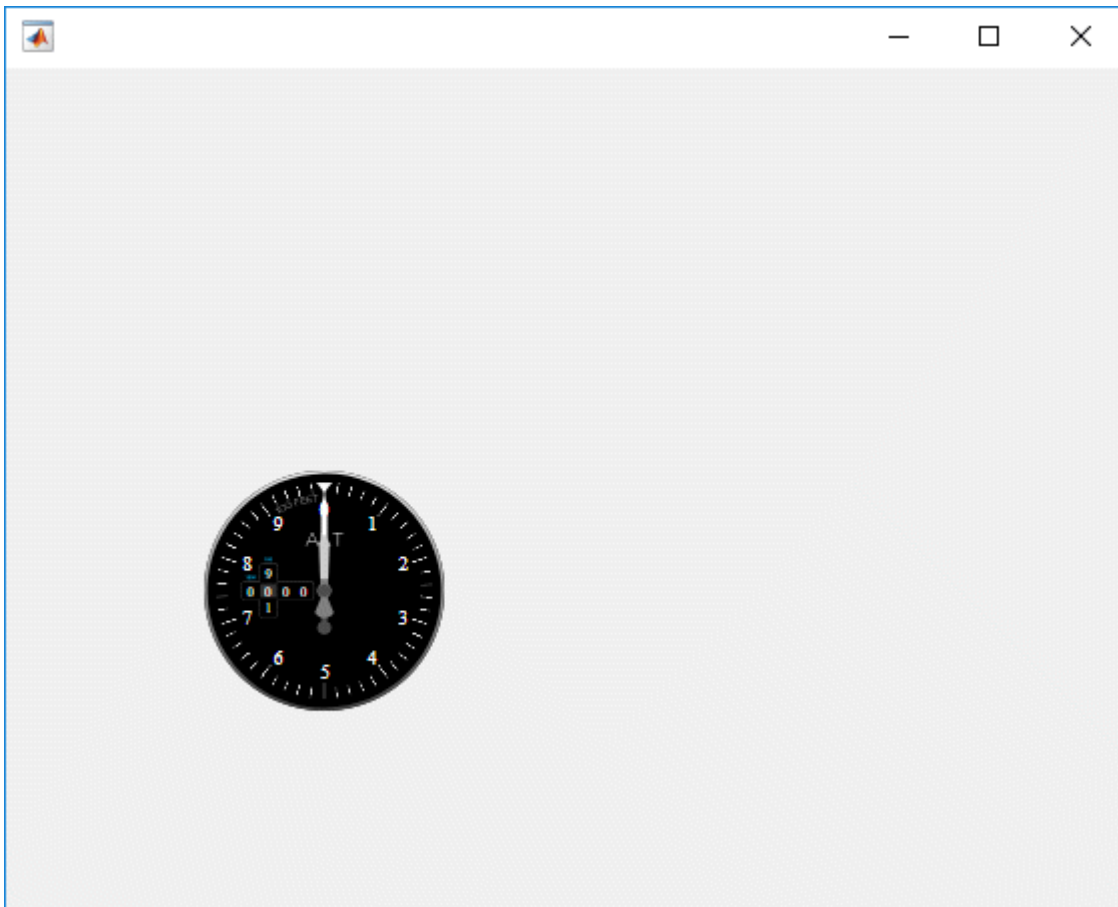
```
altimeter =
```

```
Altimeter (0) with properties:
```

```
    Altitude: 0
```

```
    Position: [100 100 120 120]
```

Show all properties



Create Figure Window and Altimeter Component

Create a figure window to contain the altimeter component, then create an altimeter component named `altimeter`.

```
f = uifigure;
```

```
altimeter = uiaeroaltimeter(f)
```

```
altimeter =

    Altimeter (0) with properties:

        Altitude: 0
        Position: [100 100 120 120]

    Show all properties
```

Input Arguments

parent — Parent container

Figure object (default) | Panel object | Tab object | ButtonGroup object | GridLayout object

Parent container, specified as a `Figure` object created using the `uifigure` function, or one of its child containers: `Tab`, `Panel`, `ButtonGroup`, or `GridLayout`. If you do not specify a parent container, MATLAB calls the `uifigure` function to create a new `Figure` object that serves as the parent container.

Name-Value Pair Arguments

Specify optional comma-separated pairs of `Name`, `Value` arguments. `Name` is the argument name and `Value` is the corresponding value. `Name` must appear inside quotes. You can specify several name and value pair arguments in any order as `Name1, Value1, . . . , NameN, ValueN`.

For a full list of `Altimeter` properties and descriptions for each type, see `Altimeter Properties`.

Output Arguments

altimeter — Altimeter component

object

Altimeter component, returned as an object.

See Also

`Altimeter Properties`

Topics

“Create and Configure Flight Instrument Component and an Animation Object” on page 2-49

“Display Flight Trajectory Data Using Flight Instruments and Flight Animation” on page 5-111

Introduced in R2018b

uiaeroclimb

Package: Aero.ui.control

Create climb rate indicator component

Syntax

```
climbrate = uiaeroclimb
climbrate = uiaeroclimb(parent)
climbrate = uiaeroclimb( ____,Name,Value)
```

Description

`climbrate = uiaeroclimb` creates a climb rate indicator in a new figure. MATLAB calls the `uifigure` function to create the figure.

The climb rate indicator displays measurements for an aircraft climb rate in ft/min.

The needle covers the top semicircle, if the velocity is positive, and the lower semicircle, if the climb rate is negative. The range of the indicator is from **-Maximum** feet per minute to **Maximum** feet per minute. Major ticks indicate **Maximum/4**. Minor ticks indicate **Maximum/8** and **Maximum/80**.

Note Use this function only with figures created using the `uifigure` function. Apps created using `GUIDE` or the `figure` function do not support flight instrument components.

`climbrate = uiaeroclimb(parent)` specifies the object in which to create the climb rate indicator.

`climbrate = uiaeroclimb(____,Name,Value)` specifies climb rate indicator properties using one or more `Name,Value` pair arguments. Use this option with any of the input argument combinations in the previous syntaxes.

Examples

Create Climb Rate Indicator Component

Create a climb rate indicator component named `climbrate`. By default, the function creates a `uifigure` object for the indicator object.

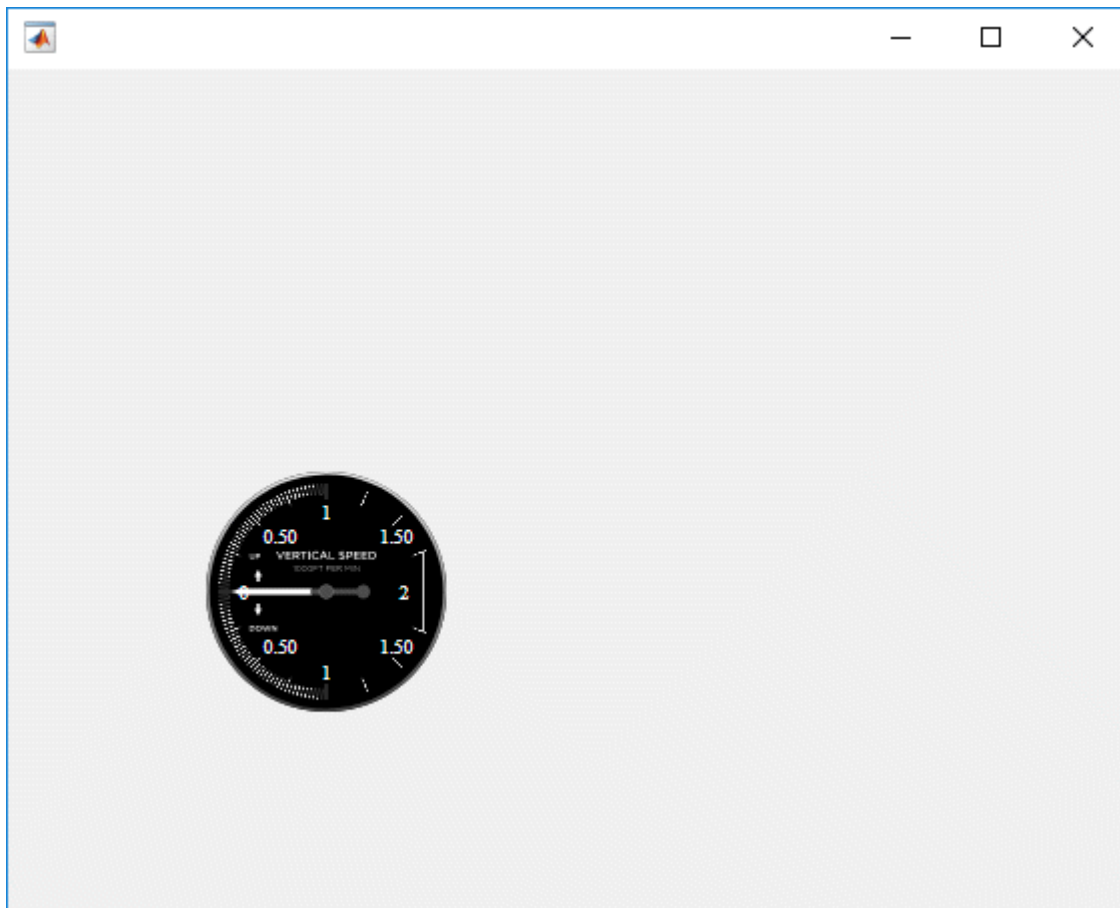
```
climbrate = uiaeroclimb
```

```
climbrate =
```

```
  ClimbIndicator (0) with properties:
```

```
    ClimbRate: 0
  MaximumRate: 2000
    Position: [100 100 120 120]
```


Show all properties



Create Figure Window and Climb Rate Indicator Component

Create a figure window to contain the climb rate indicator component, then create an climb rate indicator component named `climbrate`.

```
f = uifigure;
climbrate = uiaeroclimb(f)

climbrate =

ClimbIndicator (0) with properties:

    ClimbRate: 0
  MaximumRate: 2000
      Position: [100 100 120 120]
```

Show all properties

Input Arguments

parent — Parent container

Figure object (default) | Panel object | Tab object | ButtonGroup object | GridLayout object

Parent container, specified as a Figure object created using the `uifigure` function, or one of its child containers: `Tab`, `Panel`, `ButtonGroup`, or `GridLayout`. If you do not specify a parent container, MATLAB calls the `uifigure` function to create a new Figure object that serves as the parent container.

Name-Value Pair Arguments

Specify optional comma-separated pairs of `Name`, `Value` arguments. `Name` is the argument name and `Value` is the corresponding value. `Name` must appear inside quotes. You can specify several name and value pair arguments in any order as `Name1, Value1, . . . , NameN, ValueN`.

For a full list of climb rate indicator properties and descriptions for each type, see `ClimbIndicator Properties`.

Output Arguments

cLimbrate — Climb rate indicator component

object

Climb rate indicator component, returned as an object.

See Also

`ClimbIndicator Properties`

Topics

“Create and Configure Flight Instrument Component and an Animation Object” on page 2-49

“Display Flight Trajectory Data Using Flight Instruments and Flight Animation” on page 5-111

Introduced in R2018b

uiaeroegt

Package: Aero.ui.control

Create exhaust gas temperature (EGT) indicator component

Syntax

```
egt = uiaeroegt
egt = uiaeroegt(parent)
egt = uiaeroegt( ___,Name,Value)
```

Description

`egt = uiaeroegt` creates an EGT indicator in a new figure. MATLAB calls the `uifigure` function to create the figure.

The EGT indicator displays temperature measurements for engine exhaust gas temperature (EGT) in Celsius.

This gauge displays values using both:

- A needle on a gauge. A major tick is **(Maximum-Minimum)/1,000** degrees, a minor tick is **(Maximum-Minimum)/200** degrees Celsius.
- A numeric indicator. The operating range for the indicator goes from **Minimum** to **Maximum** degrees Celsius.

If the value of the input is under **Minimum**, the needle displays 5 degrees under the **Minimum** value, the numeric display shows the **Minimum** value. If the value exceeds the **Maximum** value, the needle displays 5 degrees over the maximum tick, and the numeric displays the **Maximum** value.

Note Use this function only with figures created using the `uifigure` function. Apps created using GUIDE or the `figure` function do not support flight instrument components.

`egt = uiaeroegt(parent)` specifies the object in which to create the EGT indicator.

`egt = uiaeroegt(___,Name,Value)` specifies EGT indicator properties using one or more `Name,Value` pair arguments. Use this option with any of the input argument combinations in the previous syntaxes.

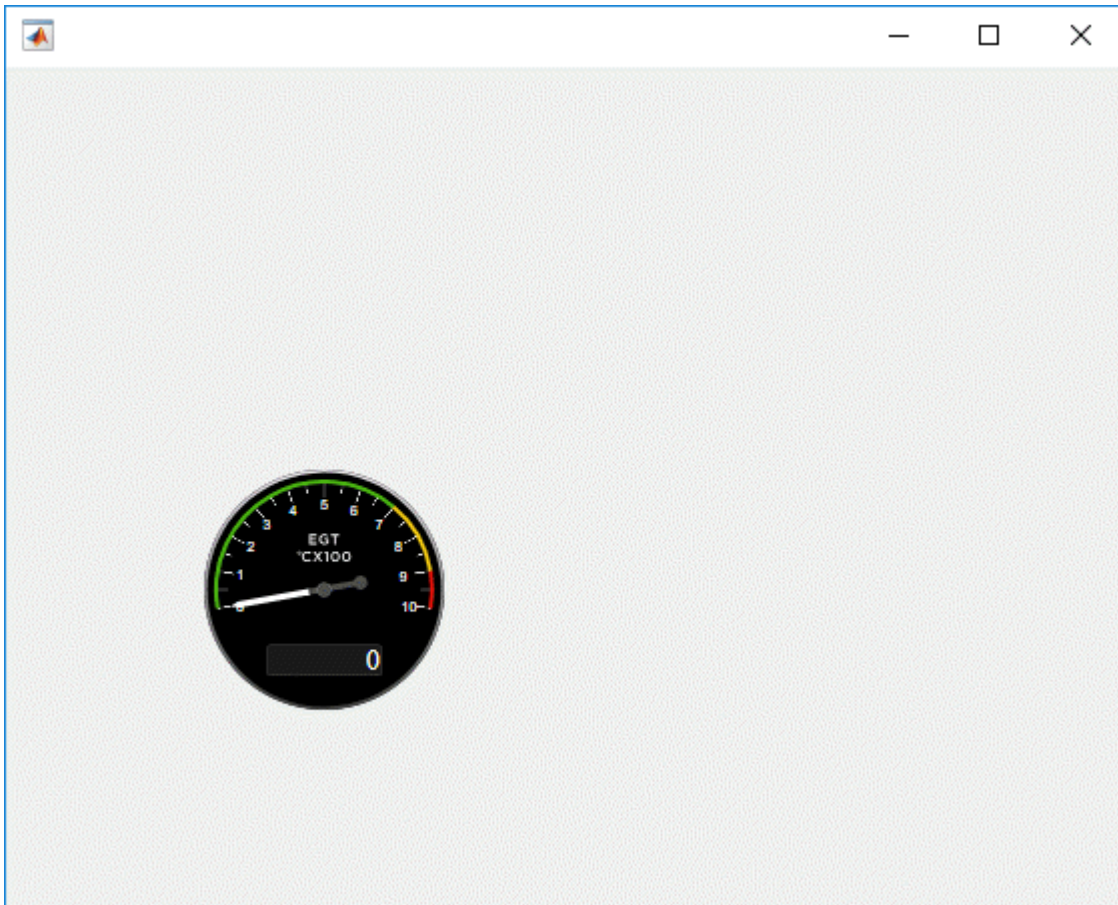
Examples

Create EGT Indicator Component

Create an EGT indicator component named `egt`. By default, the function creates a `uifigure` object for the indicator object.

```
egt = uiaeroegt
```

```
egt =  
    EGTIndicator (0) with properties:  
        Temperature: 0  
        ScaleColors: [3x3 double]  
        ScaleColorLimits: [3x2 double]  
        Limits: [0 1000]  
        Position: [100 100 120 120]  
  
Show all properties
```



Create Figure Window and EGT Indicator Component

Create a figure window to contain the EGT indicator component, then create an EGT indicator component named `egt`.

```
f = uifigure;  
egt = uiaeroegt(f)
```

```
egt =  
    EGTIndicator (0) with properties:
```

```

    Temperature: 0
    ScaleColors: [3×3 double]
    ScaleColorLimits: [3×2 double]
        Limits: [0 1000]
        Position: [100 100 120 120]

```

Show all properties

Input Arguments

parent — Parent container

Figure object (default) | Panel object | Tab object | ButtonGroup object | GridLayout object

Parent container, specified as a `Figure` object created using the `uifigure` function, or one of its child containers: `Tab`, `Panel`, `ButtonGroup`, or `GridLayout`. If you do not specify a parent container, MATLAB calls the `uifigure` function to create a new `Figure` object that serves as the parent container.

Name-Value Pair Arguments

Specify optional comma-separated pairs of `Name`, `Value` arguments. `Name` is the argument name and `Value` is the corresponding value. `Name` must appear inside quotes. You can specify several name and value pair arguments in any order as `Name1, Value1, ..., NameN, ValueN`.

For a full list of EGT indicator properties and descriptions for each type, see [EGTIndicator Properties](#).

Output Arguments

egt — EGT indicator component

object

EGT indicator component, returned as an object.

See Also

[EGTIndicator Properties](#)

Topics

“Create and Configure Flight Instrument Component and an Animation Object” on page 2-49

“Display Flight Trajectory Data Using Flight Instruments and Flight Animation” on page 5-111

Introduced in R2018b

uiaeroheading

Package: Aero.ui.control

Create heading indicator component

Syntax

```
heading = uiaeroheading
heading = uiaeroheading(parent)
heading = uiaeroheading( ____,Name,Value)
```

Description

`heading = uiaeroheading` creates a heading indicator in a new figure. MATLAB calls the `uifigure` function to create the figure.

The heading indicator displays measurements for aircraft heading in degrees.

The heading indicator represents values between 0 and 360 degrees.

Note Use this function only with figures created using the `uifigure` function. Apps created using GUIDE or the `figure` function do not support flight instrument components.

`heading = uiaeroheading(parent)` specifies the object in which to create the heading indicator.

`heading = uiaeroheading(____,Name,Value)` specifies heading indicator properties using one or more `Name,Value` pair arguments. Use this option with any of the input argument combinations in the previous syntaxes.

Examples

Create Heading Indicator Component

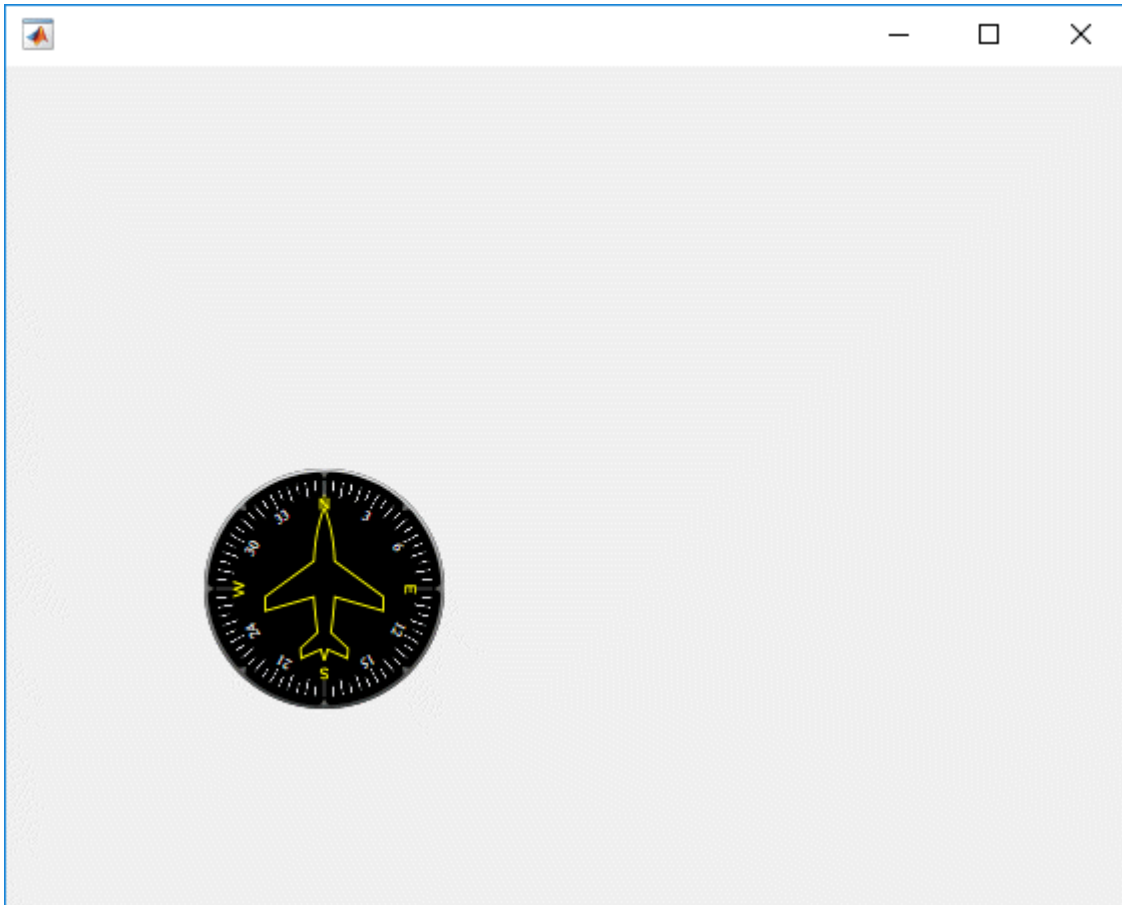
Create a heading indicator component named `heading`. By default, the function creates a `uifigure` object for the indicator object.

```
heading = uiaeroheading
```

```
heading =
```

```
HeadingIndicator (0) with properties:
```

```
    Heading: 0
    Position: [100 100 120 120]
```



Create Figure Window and Heading Indicator Component

Create a figure window to contain the heading component, then create a heading indicator component named heading.

```
f = uifigure;
heading = uiaeroheading(f)

heading =
HeadingIndicator (0) with properties:
```

```
    Heading: 0
    Position: [100 100 120 120]
```

Show all properties

Input Arguments

parent — Parent container

Figure object (default) | Panel object | Tab object | ButtonGroup object | GridLayout object

Parent container, specified as a Figure object created using the `uifigure` function, or one of its child containers: Tab, Panel, ButtonGroup, or GridLayout. If you do not specify a parent

container, MATLAB calls the `uifigure` function to create a new `Figure` object that serves as the parent container.

Name-Value Pair Arguments

Specify optional comma-separated pairs of `Name`, `Value` arguments. `Name` is the argument name and `Value` is the corresponding value. `Name` must appear inside quotes. You can specify several name and value pair arguments in any order as `Name1, Value1, . . . , NameN, ValueN`.

For a full list of heading indicator properties and descriptions for each type, see `HeadingIndicator Properties`.

Output Arguments

heading — Heading indicator component

object

Heading indicator component, returned as an object.

See Also

`HeadingIndicator Properties`

Topics

“Create and Configure Flight Instrument Component and an Animation Object” on page 2-49

“Display Flight Trajectory Data Using Flight Instruments and Flight Animation” on page 5-111

Introduced in R2018b

uiaerohorizon

Package: Aero.ui.control

Create artificial horizon component

Syntax

```
horizon = uiaerohorizon
horizon = uiaerohorizon(parent)
horizon = uiaerohorizon( ___,Name,Value)
```

Description

`horizon = uiaerohorizon` creates an artificial horizon in a new figure. MATLAB calls the `uifigure` function to create the figure.

The artificial horizon represents aircraft attitude relative to horizon and displays roll and pitch in degrees:

- Values for roll cannot exceed +/- 90 degrees.
- Values for pitch cannot exceed +/- 30 degrees.

If the values exceed the maximum values, the gauge maximum and minimum values do not change.

Changes in roll value affect the gauge semicircles and the ticks located on the black arc turn accordingly. Changes in pitch value affect the scales and the distribution of the semicircles.

Note Use this function only with figures created using the `uifigure` function. Apps created using GUIDE or the `figure` function do not support flight instrument components.

`horizon = uiaerohorizon(parent)` specifies the object in which to create the artificial horizon.

`horizon = uiaerohorizon(___,Name,Value)` specifies artificial horizon properties using one or more `Name,Value` pair arguments. Use this option with any of the input argument combinations in the previous syntaxes.

Examples

Create Artificial Horizon Component

Create an artificial horizon component named `horizon`. By default, the function creates a `uifigure` object for the indicator object.

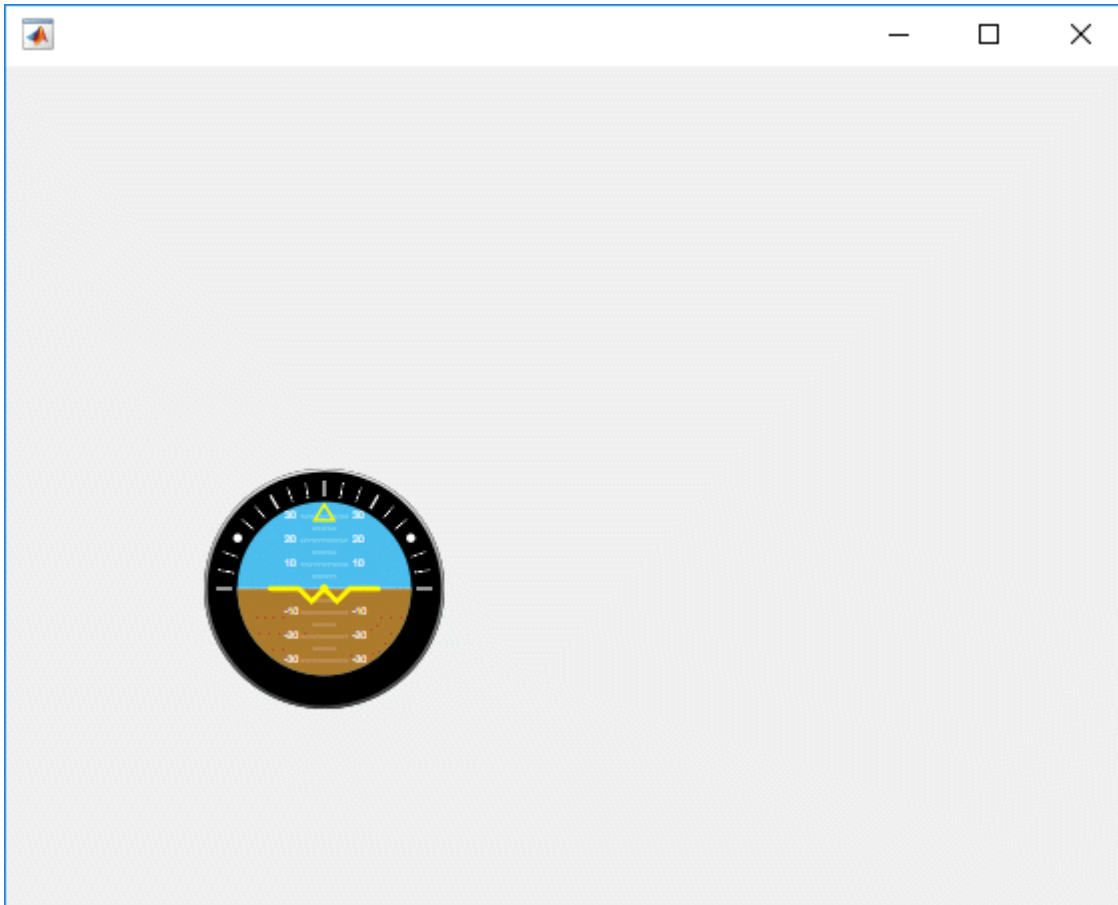
```
horizon = uiaerohorizon
```

```
horizon =
```

```
ArtificialHorizon ([0 0]) with properties:
```

```
Pitch: 0  
Roll: 0  
Position: [100 100 120 120]
```

Show all properties



Create Figure Window and Artificial Horizon Component

Create a figure window to contain the artificial horizon component, then create an artificial horizon component named horizon.

```
f = uifigure;  
egt = uiaeroegt(f)
```

```
horizon =
```

```
ArtificialHorizon ([0 0]) with properties:
```

```
Pitch: 0  
Roll: 0  
Position: [100 100 120 120]
```

Show all properties

Input Arguments

parent — Parent container

Figure object (default) | Panel object | Tab object | ButtonGroup object | GridLayout object

Parent container, specified as a Figure object created using the `uifigure` function, or one of its child containers: `Tab`, `Panel`, `ButtonGroup`, or `GridLayout`. If you do not specify a parent container, MATLAB calls the `uifigure` function to create a new Figure object that serves as the parent container.

Name-Value Pair Arguments

Specify optional comma-separated pairs of `Name`, `Value` arguments. `Name` is the argument name and `Value` is the corresponding value. `Name` must appear inside quotes. You can specify several name and value pair arguments in any order as `Name1, Value1, ..., NameN, ValueN`.

For a full list of artificial horizon properties and descriptions for each type, see `ArtificialHorizon Properties`.

Output Arguments

horizon — Artificial horizon component

object

Artificial horizon component, returned as an object.

See Also

`ArtificialHorizon Properties`

Topics

“Create and Configure Flight Instrument Component and an Animation Object” on page 2-49

“Display Flight Trajectory Data Using Flight Instruments and Flight Animation” on page 5-111

Introduced in R2018b

uiaerorpm

Package: Aero.ui.control

Create revolutions per minute (RPM) indicator component

Syntax

```
rpm = uiaerorpm
rpm = uiaerorpm(parent)
rpm = uiaerorpm( ___,Name,Value)
```

Description

`rpm = uiaerorpm` creates an RPM indicator in a new figure. MATLAB calls the `uifigure` function to create the figure.

The RPM indicator displays measurements for engine revolutions per minute in percentage of RPM.

The range of values for RPM goes from 0 to 110%. Minor ticks represent increments of 5% RPM and major ticks represent increments of 10% RPM.

Note Use this function only with figures created using the `uifigure` function. Apps created using GUIDE or the `figure` function do not support flight instrument components.

`rpm = uiaerorpm(parent)` specifies the object in which to create the RPM indicator.

`rpm = uiaerorpm(___,Name,Value)` specifies RPM indicator properties using one or more `Name,Value` pair arguments. Use this option with any of the input argument combinations in the previous syntaxes.

Examples

Create RPM Indicator Component

Create an RPM indicator component named `rpm`. By default, the function creates a `uifigure` object for the indicator object.

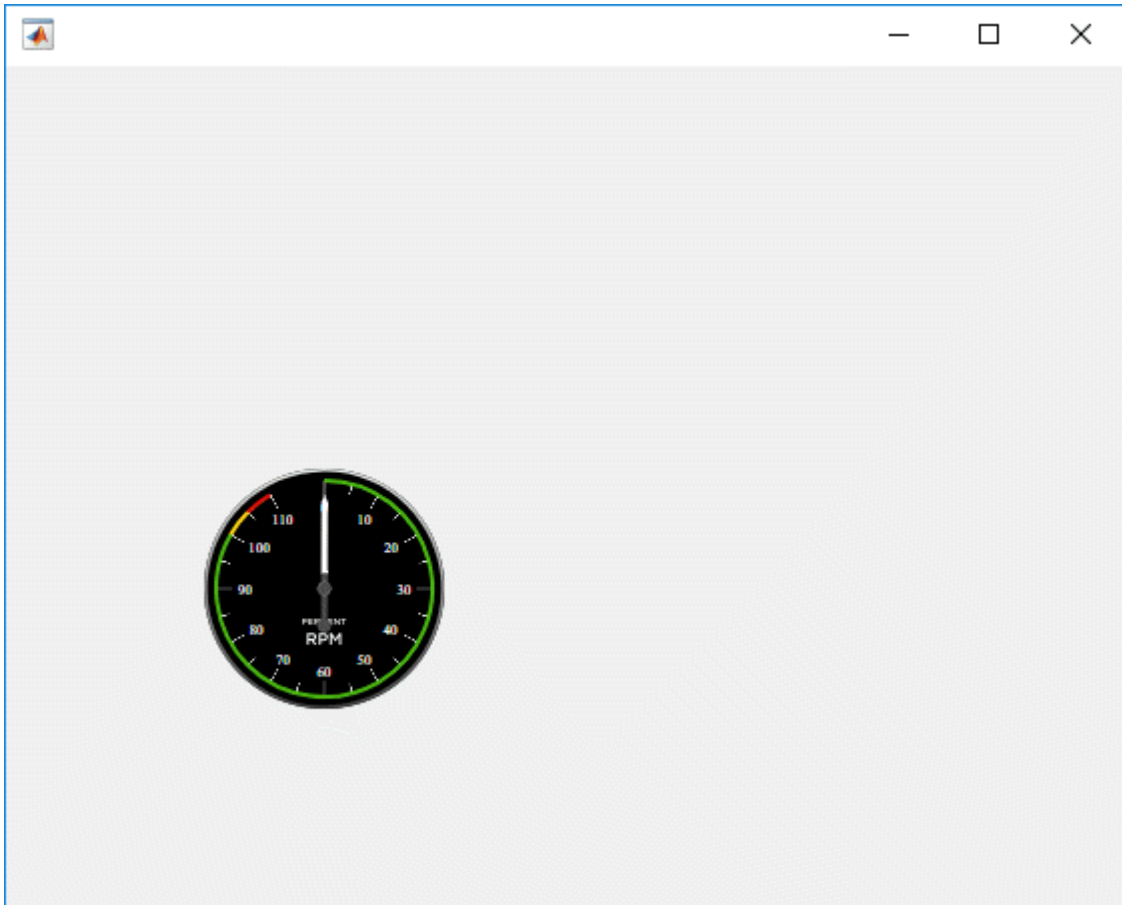
```
rpm = uiaerorpm
```

```
rpm =
```

```
  RPMIndicator (0) with properties:
```

```
      RPM: 0
  ScaleColors: [3x3 double]
ScaleColorLimits: [3x2 double]
      Position: [100 100 120 120]
```

```
Show all properties
```



Create Figure Window and RPM Indicator Component

Create a figure window to contain the RPM indicator component, then create an RPM indicator component named `rpm`.

```
f = uifigure;
rpm = uiaerorpm(f)

rpm =

    RPMIndicator (0) with properties:
        RPM: 0
        ScaleColors: [3x3 double]
        ScaleColorLimits: [3x2 double]
        Position: [100 100 120 120]

    Show all properties
```

Input Arguments

parent — Parent container

Figure object (default) | Panel object | Tab object | ButtonGroup object | GridLayout object

Parent container, specified as a `Figure` object created using the `uifigure` function, or one of its child containers: `Tab`, `Panel`, `ButtonGroup`, or `GridLayout`. If you do not specify a parent container, MATLAB calls the `uifigure` function to create a new `Figure` object that serves as the parent container.

Name-Value Pair Arguments

Specify optional comma-separated pairs of `Name`, `Value` arguments. `Name` is the argument name and `Value` is the corresponding value. `Name` must appear inside quotes. You can specify several name and value pair arguments in any order as `Name1, Value1, . . . , NameN, ValueN`.

For a full list of RPM indicator properties and descriptions for each type, see `RPMIndicator Properties`.

Output Arguments

rpm — RPM indicator

object

RPM indicator component, returned as an object.

See Also

`RPMIndicator Properties`

Topics

“Create and Configure Flight Instrument Component and an Animation Object” on page 2-49

“Display Flight Trajectory Data Using Flight Instruments and Flight Animation” on page 5-111

Introduced in R2018b

uiaereturn

Package: Aero.ui.control

Create turn coordinator component

Syntax

```
turn = uiaereturn
turn = uiaereturn(parent)
turn = uiaereturn( ____,Name,Value)
```

Description

`turn = uiaereturn` creates a turn coordinator in a new figure. MATLAB calls the `uifigure` function to create the figure.

The `uiaereturn` function displays measurements on a gyroscopic turn rate instrument and on an inclinometer.

- The gyroscopic turn rate instrument shows the rate of heading change of the aircraft as a tilting of the aircraft symbol in the gauge.
- The inclinometer shows whether the turn is coordinated, slipping, or skidding by the position of the ball.

When the ball is centered, the turn is coordinated. When the ball is off center, the turn is slipping or skidding. The turn rate instrument has marks for wings level and for a standard rate turn. A standard rate turn is a heading change of 3 degrees per second, also known as a two minute turn.

The input for gyroscopic turn rate instruments and inclinometers is in degrees. The turn rate value is input as the degrees of tilt of the aircraft symbol in the gauge. The standard rate turn marks are at angles of ± 15 degrees. Tilt angle values are limited to ± 20 degrees, whereas inclinometer angles are limited to ± 15 degrees.

For example, turn indicator and inclinometer values of `[15 0]` indicate a coordinated, standard rate turn.

Note Use this function only with figures created using the `uifigure` function. Apps created using GUIDE or the `figure` function do not support flight instrument components.

`turn = uiaereturn(parent)` specifies the object in which to create the turn coordinator.

`turn = uiaereturn(____,Name,Value)` specifies turn coordinator properties using one or more `Name,Value` pair arguments. Use this option with any of the input argument combinations in the previous syntaxes.

Examples

Create Turn Coordinator Component

Create a turn coordinator component named `turn`.

```
turn = uiaereturn
```

```
turn =
```

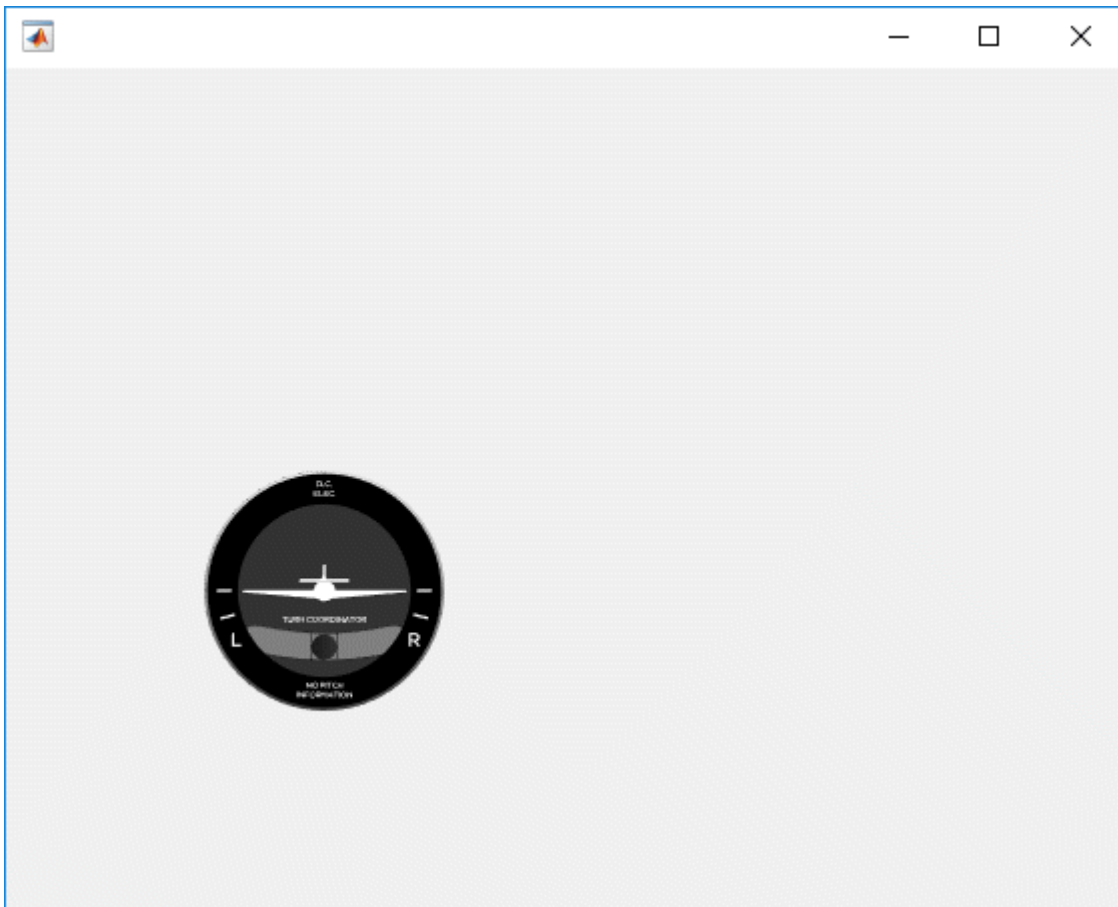
```
TurnCoordinator ([0 0]) with properties:
```

```
    Turn: 0
```

```
    Slip: 0
```

```
    Position: [100 100 120 120]
```

```
Show all properties
```



Create Figure Window and Turn Coordinator Component

Create a figure window to contain the turn coordinator component, then create a turn coordinator component named `turn`.

```
f = uifigure;
```

```
turn = uiaereturn(f)
```



```

turn =
    TurnCoordinator ([0 0]) with properties:
        Turn: 0
        Slip: 0
        Position: [100 100 120 120]

Show all properties

```

Input Arguments

parent — Parent container

Figure object (default) | Panel object | Tab object | ButtonGroup object | GridLayout object

Parent container, specified as a `Figure` object created using the `uifigure` function, or one of its child containers: `Tab`, `Panel`, `ButtonGroup`, or `GridLayout`. If you do not specify a parent container, MATLAB calls the `uifigure` function to create a new `Figure` object that serves as the parent container.

Name-Value Pair Arguments

Specify optional comma-separated pairs of `Name`, `Value` arguments. `Name` is the argument name and `Value` is the corresponding value. `Name` must appear inside quotes. You can specify several name and value pair arguments in any order as `Name1, Value1, ..., NameN, ValueN`.

For a full list of turn coordinator properties and descriptions for each type, see `TurnCoordinator Properties`.

Output Arguments

turn — Turn coordinator component

object

Turn coordinator component, returned as an object.

See Also

`TurnCoordinator Properties`

Topics

“Create and Configure Flight Instrument Component and an Animation Object” on page 2-49

“Display Flight Trajectory Data Using Flight Instruments and Flight Animation” on page 5-111

Introduced in R2018b

update

Class: Aero.FixedWing

Package: Aero

Update Aero.FixedWing object

Syntax

```
aircraft = update(aircraft)
aircraft = update(aircraft,Rename,Value)
```

Description

`aircraft = update(aircraft)` returns the modified coefficient Aero.FixedWing object.

`aircraft = update(aircraft,Rename,Value)` updates the Name property in the Simulink.lookupable.StructTypeInfo object of each Simulink.LookupTable coefficient in the Aero.FixedWing object hierarchy. The updated name is a compilation of all component Name values in the Aero.FixedWing hierarchy, with this format:

- Listed in descending order
- Separated by underscores (_)
- Appended by the stateOutput and stateVariable values of each Simulink.LookupTable location

Input Arguments

aircraft — Aero.FixedWing coefficient object

scalar | Aero.FixedWing | Aero.FixedWing.Surface | Aero.FixedWing.Control | Aero.FixedWing.Thrust | Aero.FixedWing.Coefficient

Aero.FixedWing coefficient object, specified as a scalar, of type Aero.FixedWing, Aero.FixedWing.Surface, Aero.FixedWing.Control, Aero.FixedWing.Thrust, or Aero.FixedWing.Coefficient.

Rename, Value — Option to update Name property in Simulink.lookupable.StructTypeInfo object

on (default) | off

Option to update the Name property in the Simulink.lookupable.StructTypeInfo object, specified as:

- 'on' — To modify the Name property in the Simulink.lookupable.StructTypeInfo object.
- 'off' — Do not modify the Name field in the Simulink.lookupable.StructTypeInfo object.

Example: 'Rename', 'on'

Data Types: string | char

Output Arguments

aircraft — Modified Aero.FixedWing object

scalar

Modified Aero.FixedWing object with the modified coefficients at the specified locations, returned as a scalar.

Examples

Update Aircraft Name and View Updated Coefficients

Update the aircraft name and view the updated coefficients.

```
aircraft = astSkyHogg;  
aircraft.Properties.Name = 'NewName';  
aircraft = update(aircraft);  
aircraft.Coefficients.Values{1}.StructTypeInfo.Name  
  
ans =  
  
    'NewName_CD_Zero'
```

Update Aircraft Name But Do Not Propagate

Update the aircraft name, but do not propagate the new name to the coefficients.

```
aircraft = astSkyHogg;  
aircraft.Properties.Name = 'NewName';  
aircraft = update(aircraft, 'Rename', 'off');  
aircraft.Coefficients.Values{1}.StructTypeInfo.Name  
  
ans =  
  
    'SkyHogg_CD_Zero'
```

See Also

[Aero.FixedWing](#) | [Simulink.LookupTable](#) | [Simulink.lookuptable.StructTypeInfo](#) | [getCoefficient](#) | [setCoefficient](#)

Topics

“Determine Nonlinear Dynamics and Static Stability of Fixed-Wing Aircraft” on page 5-128

“Perform Controls and Static Stability Analysis with Linearized Fixed-Wing Aircraft” on page 5-115

“Customize Fixed-Wing Aircraft with Additional Aircraft States” on page 5-122

Introduced in R2021a

update

Class: Aero.FixedWing.Coefficient

Package: Aero

Update Aero.FixedWing.Coefficient object

Syntax

```
FixedWingCoefficient = update(FixedWingCoefficient,Rename,Value)
```

Description

`FixedWingCoefficient = update(FixedWingCoefficient,Rename,Value)` updates the Aero.FixedWing.Coefficient object.

Input Arguments

FixedWingCoefficient — Aero.FixedWingCoefficient object

scalar

Aero.FixedWing.Coefficient object, specified as a scalar.

Rename, Value — Option to update Name property in Simulink.lookuptable.StructTypeInfo object

on (default) | off

Option to update the Name property in the Simulink.lookuptable.StructTypeInfo object, specified as:

- 'on' — Modify the Name property in the Simulink.lookuptable.StructTypeInfo object.

This method sets the Name property in the Simulink.lookuptable.StructTypeInfo objects to `name_stateOutput_stateVariable`, where:

- `name` is the combined string from the component name joined with all component names above it.
- `stateOutput` and `stateVariable` are the `stateOutput` and `stateVariable` values from each specific Simulink.LookupTable location, respectively.
- 'off' — Do not modify the Name field in the Simulink.lookuptable.StructTypeInfo object.

Example: 'Rename', 'on'

Data Types: string | char

Output Arguments

FixedWingCoefficient — Modified Aero.FixedWing.Coefficient object

scalar

Modified `Aero.FixedWing.Coefficient` object with modified coefficients at the specified locations, specified as a scalar.

See Also

`Aero.FixedWing` | `Simulink.lookuptable.StructTypeInfo`

Introduced in R2021a

update

Class: Aero.FixedWing.Surface

Package: Aero

Update Aero.FixedWing.Surface object

Syntax

```
FixedWingSurface = update(FixedWingSurface, Rename, Value)
```

Description

FixedWingSurface = update(FixedWingSurface, Rename, Value) updates the surface object FixedWingSurface.

Input Arguments

FixedWingSurface — Aero.FixedWingSurface object

scalar

Aero.FixedWingSurface surface object, specified as a scalar.

Rename, Value — Option to update Name property in Simulink.lookuptable.StructTypeInfo object

on (default) | off

Option to update the Name property in the Simulink.lookuptable.StructTypeInfo object, specified as:

- 'on' — Modify the Name property in the Simulink.lookuptable.StructTypeInfo object.

The method sets the Name property in the Simulink.lookuptable.StructTypeInfo objects to name_stateOutput_stateVariable, where:

- name is the combined string from the component name joined with all component names above it.
- stateOutput and stateVariable are the stateOutput and stateVariable values from each specific Simulink.LookupTable location, respectively.
- 'off' — Do not modify the Name field in the Simulink.lookuptable.StructTypeInfo object.

Example: 'Rename', 'on'

Data Types: string | char

Output Arguments

FixedWingSurface — Modified Aero.FixedWing.Surface object

scalar

Modified `Aero.FixedWing.Surface` object with the modified coefficients at the specified locations, returned as a scalar.

See Also

`Aero.FixedWing` | `Simulink.lookuptable.StructTypeInfo`

Introduced in R2021a

update

Class: Aero.FixedWing.Thrust

Package: Aero

Update Aero.FixedWing.Thrust object

Syntax

```
FixedWingThrust = update(FixedWingThrust,Rename,Value)
```

Description

FixedWingThrust = update(FixedWingThrust,Rename,Value) updates the Aero.FixedWingThrust object.

Input Arguments

FixedWingThrust — Aero.FixedWingThrust object

scalar

Aero.FixedWingThrust thrust object, specified as a scalar.

Rename, Value — Option to update Name property in Simulink.lookupable.StructTypeInfo object

on (default) | off

Option to update the Name property in the Simulink.lookupable.StructTypeInfo object, specified as:

- 'on' — Modify the Name property in the Simulink.lookupable.StructTypeInfo object.

The method sets the Name property in the Simulink.lookupable.StructTypeInfo objects to name_stateOutput_stateVariable, where:

- name is the combined string from the component name joined with all component names above it.
- stateOutput and stateVariable are the stateOutput and stateVariable values from each specific Simulink.LookupTable location, respectively.
- 'off' — Do not modify the Name field in the Simulink.lookupable.StructTypeInfo object.

Example: 'Rename', 'on'

Data Types: string | char

Output Arguments

FixedWingThrust — Modified Aero.FixedWing.Thrust object

Aero.FixedWing.Thrust

Modified Aero.FixedWingThrust object with the modified coefficients at the specified locations.

See Also

`Aero.FixedWing` | `Simulink.lookuptable.StructTypeInfo`

Introduced in R2021a

update (Aero.Body)

Change body position and orientation as function of time

Syntax

```
update(h,t)
h.update(t)
```

Description

update(h,t) and h.update(t) change body position and orientation of body h as a function of time t. t is a scalar in seconds.

Note This function requires that you load the body geometry and time series data first.

Examples

Update the body b with time in seconds of 5.

```
b=Aero.Body;
b.load('pa24-250_orange.ac','Ac3d');
tsdata = [ ...
    0, 1,1,1, 0,0,0; ...
    10 2,2,2, 1,1,1; ];
b.TimeSeriesSource = tsdata;
b.update(5);
```

See Also

load

Introduced in R2007a

update (Aero.Camera)

Update camera position based on time and position of other Aero.Body objects

Syntax

```
update(h,newtime,bodies)  
h.update(newtime,bodies)
```

Description

`update(h,newtime,bodies)` and `h.update(newtime,bodies)` update the camera object, `h`, position and aim point data based on the new time, `newtime`, and position of other Aero.Body objects, `bodies`. This function updates the camera object `PrevTime` property to `newtime`.

See Also

`play`

Introduced in R2007a

update (Aero.FlightGearAnimation)

Update position data to FlightGear animation object

Syntax

```
update(h,time)
h.update(time)
```

Description

`update(h,time)` and `h.update(time)` update the position data to the FlightGear animation object via UDP. It sets the new position and attitude of body `h`. `time` is a scalar in seconds.

Note This function requires that you load the time series data and run FlightGear first.

Examples

Configure a body with `TimeSeriesSource` set to `simdata`, then update the body with time `time` equal to 0.

```
h = Aero.FlightGearAnimation;
h.FramesPerSecond = 10;
h.TimeScaling = 5;
load simdata;
h.TimeSeriesSource = simdata;
t = 0;
h.update(t);
```

See Also

`GenerateRunScript` | `initialize` | `play`

Introduced in R2007a

update (Aero.Node)

Change node position and orientation versus time data

Syntax

```
update(h,t)
h.update(t)
```

Description

update(h,t) and h.update(t) change node position and orientation of node h as a function of time t. t is a scalar in seconds.

Note This function requires that you load the node and time series data first.

Examples

Move the Lynx body.

```
h = Aero.VirtualRealityAnimation;
h.FramesPerSecond = 10;
h.TimeScaling = 5;
h.VRWorldFilename = [matlabroot,'/toolbox/aero/astdemos/asttkoff.wrl'];
copyfile(h.VRWorldFilename,[tempdir,'asttkoff.wrl'],'f');
h.VRWorldFilename = [tempdir,'asttkoff.wrl'];
h.initialize();
load takeoffData
h.Nodes{7}.TimeseriesSource = takeoffData;
h.Nodes{7}.TimeseriesSourceType = 'StructureWithTime';
h.Nodes{7}.update(5);
```

See Also

updateNodes

Introduced in R2007b

updateBodies

Class: Aero.Animation

Package: Aero

Update bodies of animation object

Syntax

```
h = updateBodies(time)
h.updateBodies(time)
```

Description

`h = updateBodies(time)` and `h.updateBodies(time)` set the new position and attitude of movable bodies in the animation object `h`. This function updates the bodies contained in the animation object `h`. `time` is a scalar in seconds.

Examples

Configure a body with `TimeSeriesSource` set to `simdata`, then update the body with time `t` equal to 0.

```
h = Aero.Animation;
h.FramesPerSecond = 10;
h.TimeScaling = 5;
idx1 = h.createBody('pa24-250_orange.ac', 'Ac3d');
load simdata;
h.Bodies{1}.TimeSeriesSource = simdata;
t = 0;
h.updateBodies(t);
```

updateCamera

Class: Aero.Animation

Package: Aero

Update camera in animation object

Syntax

```
updateCamera(h,time)
h.updateCamera(time)
```

Description

`updateCamera(h,time)` and `h.updateCamera(time)` update the camera in the animation object `h`. `time` is a scalar in seconds.

Note The `PositionFcn` property of a camera object controls the camera position relative to the bodies in the animation. The default camera `PositionFcn` follows the path of a first order chase vehicle. Therefore, it takes a few steps for the camera to position itself correctly in the chase plane position.

Input Arguments

<code>h</code>	Animation object.
<code>time</code>	Scalar in seconds.

Examples

Configure a body with `TimeSeriesSource` set to `simdata`, then update the camera with time `t` equal to 0.

```
h = Aero.Animation;
h.FramesPerSecond = 10;
h.TimeScaling = 5;
idx1 = h.createBody('pa24-250_orange.ac','Ac3d');
load simdata;
h.Bodies{1}.TimeSeriesSource = simdata;
t = 0;
h.updateCamera(t);
```

updateNodes (Aero.VirtualRealityAnimation)

Change virtual reality animation node position and orientation as function of time

Syntax

```
updateNodes(h,t)  
h.updateNotes(t)
```

Description

`updateNodes(h,t)` and `h.updateNotes(t)` change node position and orientation of body `h` as a function of time `t`. `t` is a scalar in seconds.

Note This function requires that you load the node and time series data first.

Examples

Update the node `h` with time in 5 seconds.

```
h = Aero.VirtualRealityAnimation;  
h.FramesPerSecond = 10;  
h.TimeScaling = 5;  
h.VRWorldFilename = [matlabroot,'/toolbox/aero/astdemos/asttkoff.wrl'];  
copyfile(h.VRWorldFilename,[tempdir,'asttkoff.wrl'],'f');  
h.VRWorldFilename = [tempdir,'asttkoff.wrl'];  
h.initialize();  
load takeoffData  
h.Nodes{7}.TimeseriesSource = takeoffData;  
h.Nodes{7}.TimeseriesSourceType = 'StructureWithTime';  
h.Nodes{7}.CoordTransformFcn = @vranimCustomTransform;  
h.updateNodes(5);
```

See Also

[addNode](#) | [update](#)

Introduced in R2007b

Viewpoint (Aero.Viewpoint)

Create viewpoint object for use in virtual reality animation

Syntax

```
h = Aero.Viewpoint
```

Description

`h = Aero.Viewpoint` creates a viewpoint object for use with virtual reality animation.

See `Aero.Viewpoint` for further details.

Introduced in R2007b

VirtualRealityAnimation (Aero.VirtualRealityAnimation)

Construct virtual reality animation object

Syntax

```
h = Aero.VirtualRealityAnimation
```

Description

`h = Aero.VirtualRealityAnimation` constructs a virtual reality animation object. The animation object is returned to `h`.

See `Aero.VirtualRealityAnimation` for further details.

See Also

`Aero.VirtualRealityAnimation`

Introduced in R2007b

wrldmagm

Use World Magnetic Model

Syntax

```
[XYZ,H,D,I,F] = wrldmagm(height,latitude,longitude,decimalYear)
[XYZ,H,D,I,F] = wrldmagm(height,latitude,longitude,decimalYear,model)
[XYZ,H,D,I,F] = wrldmagm(height,latitude,longitude,decimalYear,
'Custom',filename)
```

Description

[XYZ,H,D,I,F] = wrldmagm(height,latitude,longitude,decimalYear) calculates the Earth magnetic field at a specific location and time using the World Magnetic Model (WMM) WMM2020.

[XYZ,H,D,I,F] = wrldmagm(height,latitude,longitude,decimalYear,model) calculates the Earth magnetic field using World Magnetic Model model.

[XYZ,H,D,I,F] = wrldmagm(height,latitude,longitude,decimalYear, 'Custom', filename) calculates the Earth magnetic field using the World Magnetic Model defined in the WMM.cof file. The WMM.cof files must be in their original form as provided by NOAA.

Examples

Calculate Magnetic Model Using WMM2020

Calculate the magnetic model 1000 meters over Natick, Massachusetts, on July 4, 2020, using the WMM2020 model.

```
[XYZ, H, D, I, F] = wrldmagm(1000, 42.283, -71.35, decyear(2020,7,4), '2020')
```

```
XYZ =
    1.0e+04 *
    1.9738
   -0.5014
    4.7556
```

```
H =
    2.0364e+04
```

```
D =
   -14.2536
```

```
I =
    66.8184
```

```
F =  
  5.1733e+04
```

Calculate Magnetic Model for Downloaded WMM2020.COF file

Calculate the magnetic model 1000 meters over Natick, Massachusetts, on July 4, 2020, using a downloaded WMM2020.COF file.

```
[XYZ, H, D, I, F] = wrldmagm(1000, 42.283, -71.35, decyear(2020,7,4), 'Custom', 'WMM2020.COF')
```

```
XYZ =  
  1.0e+04 *  
  
  1.9738  
 -0.5014  
  4.7556
```

```
H =  
  2.0364e+04
```

```
D =  
 -14.2536
```

```
I =  
  66.8184
```

```
F =  
  5.1733e+04
```

Input Arguments

height — Distance

scalar

Distance from the surface of the Earth, specified as a scalar, in meters.

Data Types: double

latitude — Geodetic latitude

scalar

Geodetic latitude, specified as a scalar, in degrees. North latitude is positive and south latitude is negative.

This function accepts latitude values greater than 90 and less than -90.

Data Types: double

longitude — Geodetic longitude

scalar

Geodetic longitude, specified as a scalar, in degrees. East longitude is positive and west longitude is negative. This function accepts longitude values greater than 180 and less than -180.

Data Types: double

decimalYear — Decimal year

scalar

Year, in decimal format, specified as a scalar. This value can have any fraction of the year that has already passed.

Data Types: double

model — World Magnetic Model

'2020' (default) | '2015v2' | '2015' | '2015v1' | '2010' | '2005' | '2000' | character vector | string

World Magnetic Model, specified as a character vector or string.

Model	Description
'2020'	WMM2020 (epoch 2020–2025).
'2015v2' or '2015'	WMM2015v2 (epoch 2015–2020).
'2015v1'	WMM2015 (epoch 2015–2020). This version is not recommended. Use '2015v2' (WMM2015v2) instead.
'2010'	WMM2010 (epoch 2010–2015).
'2005'	WMM2005 (epoch 2005–2010).
'2000'	WMM2000 (epoch 2000–2005).

Data Types: char | string

'Custom', filename — Coefficient file

coefficient file name

Coefficient file, WMM.COF, downloaded from <https://www.ngdc.noaa.gov/geomag/WMM/DoDWMM.shtml>.

Example: 'Custom', 'WMM.COF'

Data Types: char | string

Output Arguments**XYZ — Magnetic field vector**

vector

Magnetic field vector, returned as a vector, in nanotesla.

H — Horizontal intensity

scalar

Horizontal intensity, returned as a scalar, in nanotesla.

D — Declination

scalar

Declination, returned as a scalar, in degrees (+ve east).

I – Inclination

scalar

Inclination, returned as a scalar, in degrees (+ve down).

F – Total intensity

scalar

Total intensity, returned as a scalar, in nanotesla (nT).

Limitations

- The WMM specification produces data that is reliable five years after the epoch of the model, which begins January 1 of the model year selected. The WMM specification describes only the long-wavelength spatial magnetic fluctuations due to the Earth core. Intermediate and short-wavelength fluctuations, contributed from the crustal field (the mantle and crust), are not included. Also, the substantial fluctuations of the geomagnetic field, which occur constantly during magnetic storms and almost constantly in the disturbance field (auroral zones), are not included.
- This function has the limitations of the World Magnetic Model (WMM). WMM2020 is valid between -1km and 850km, as outlined in the World Magnetic Model 2020 Technical Report.
- WMM2015v2 was released by NOAA in February, 2019 to correct performance degradation issues in the Arctic region from January 1, 2015 to December 31, 2019. WMM2015v2 supersedes WMM2015. Consider replacing WMM2015 with WMM2015v2 for use with navigation and other systems. It is still acceptable to use WMM2015 in systems below 55 degrees latitude in the Northern hemisphere.

See Also

decyear | igrfmagm

External Websites

<https://www.ngdc.noaa.gov/geomag/WMM/DoDWMM.shtml>

Introduced in R2006b

Bodies property

Class: Aero.Animation

Package: Aero

Specify name of animation object

Values

MATLAB array

Default: []

Description

This property specifies the bodies that the animation object contains.

Camera property

Class: Aero.Animation

Package: Aero

Specify camera that animation object contains

Values

handle

Default: []

Description

This property specifies the camera that the animation object contains.

Figure property

Class: Aero.Animation

Package: Aero

Specify name of figure object

Values

MATLAB array

Default: []

Description

This property specifies the name of the figure object.

FigureCustomizationFcn property

Class: Aero.Animation

Package: Aero

Specify figure customization function

Values

MATLAB array

Default: []

Description

This property specifies the figure customization function.

FramesPerSecond property

Class: Aero.Animation

Package: Aero

Animation rate

Values

MATLAB array

Default: 12

Description

This property specifies rate in frames per second.

Name property

Class: Aero.Animation

Package: Aero

Specify name of animation object

Values

Character vector | string

Default: ' '

Description

This property specifies the name of the animation object.

TCurrent property

Class: Aero.Animation

Package: Aero

Current time

Values

double

Default: 0

Description

This property specifies the current time.

TFinal property

Class: Aero.Animation

Package: Aero

End time

Values

double

Default: NaN

Description

This property specifies the end time.

TimeScaling property

Class: Aero.Animation

Package: Aero

Scaling time

Values

double

Default: 1

Description

This property specifies the time, in seconds.

TStart property

Class: Aero.Animation

Package: Aero

Start time

Values

double

Default: NaN

Description

This property specifies the start time.

VideoCompression property

Class: Aero.Animation

Package: Aero

Video recording compression file type

Values

'Archival'

Create Motion JPEG 2000 format file with lossless compression.

'Motion JPEG AVI'

Create compressed AVI format file using Motion JPEG codec.

'Motion JPEG 2000'

Create compressed Motion JPEG 2000 format file.

'MPEG-4'

Create compressed MPEG-4 format file with H.264 encoding (Windows 7 systems only).

'Uncompressed AVI'

Create uncompressed AVI format file with RGB24 video.

Data type: Aero.VideoProfileTypeEnum

Default: 'Archival'

Description

This property specifies the compression file type to create. For more information on video compression, see [VideoWriter](#).

VideoFileName property

Class: Aero.Animation

Package: Aero

Video recording file name

Values

filename

Data type: character vector | string

Default: temp

Description

This property specifies the file name for the video recording.

VideoQuality property

Class: Aero.Animation

Package: Aero

Video recording quality

Values

Value between 0 and 100

Data type: double

Default: 75

Description

This property specifies the recording quality. For more information on video quality, see the [Quality](#) property in [VideoWriter](#).

VideoRecord property

Class: Aero.Animation

Package: Aero

Video recording

Values

'on'

Enable video recording.

'off'

Disable video recording.

'scheduled'

Schedule video recording. Use this setting with the VideoTStart and VideoTFinal properties.

Data type: character vector | string

Default: 'off'

Description

This property enables video recording of animation objects.

If you are capturing frames of a plot that takes a long time to generate or are repeatedly capturing frames in a loop, make sure that your computer's screen saver does not activate and that your monitor does not turn off for the duration of the capture; otherwise one or more of the captured frames can contain graphics from your screen saver or nothing at all.

Note In situations where MATLAB software is running on a virtual desktop that is not currently visible on your monitor, it may capture a region on your monitor that corresponds to the position occupied by the figure or axes on the hidden desktop. Therefore, make sure that the window to be captured exists on the currently active desktop.

Examples

Record Animation Object Simulation

Simulate and record flight data. Create an animation object.

```
h = Aero.Animation;
```

Control the frame display rate.

```
h.FramesPerSecond = 10;
```

Set the time-scaling (`TimeScaling`) property on the animation object to specify the data per second.

```
h.TimeScaling = 5;
```

The combination of `FramesPerSecond` and `TimeScaling` properties determines the time step of the simulation. These settings result in a time step of approximately 0.5 s.

Create and load a body for the animation object.

```
idx1 = h.createBody('pa24-250_orange.ac', 'Ac3d');
```

Load simulated flight trajectory data (`simdata`), located in `matlabroot\toolbox\ aero \astdemos`.

```
load simdata;
```

Set the time series data for the body.

```
h.Bodies{1}.TimeSeriesSource = simdata;
```

Create a figure object for the animation object.

```
h.show();
```



Set up recording properties.

```
h.VideoRecord = 'on';  
h.VideoQuality = 50;  
h.VideoCompression = 'Motion JPEG AVI'
```

```
h =
  Animation with properties:
      Name: ''
      Figure: [1×1 Figure]
  FigureCustomizationFcn: []
      Bodies: {[1×1 Aero.Body]}
      Camera: [1×1 Aero.Camera]
  TimeScaling: 5
      TStart: NaN
      TFinal: NaN
      TCurrent: 0
  FramesPerSecond: 10
  VideoRecord: 'on'
  VideoFileName: 'temp'
  VideoCompression: 'Motion JPEG AVI'
  VideoQuality: 50
  VideoTStart: NaN
  VideoTFinal: NaN
```

```
h.VideoFilename = 'astMotion_JPEG';
```

Play the animation.

```
h.play();
```

Verify that a file named `astMotion_JPEG.avi` was created in the current folder.

Disable recording to preserve the file.

```
h.VideoRecord = 'off';
```

Record Animation for Four Seconds

Simulate flight data for four seconds. Create an animation object.

```
h = Aero.Animation;
```

Control the frame display rate.

```
h.FramesPerSecond = 10;
```

Configure the animation object to set the seconds of animation data per second time-scaling (`TimeScaling`) property.

```
h.TimeScaling = 5;
```

The combination of `FramesPerSecond` and `TimeScaling` properties determines the time step of the simulation (`TimeScaling/|FramesPerSecond|`). These settings result in a time step of approximately 0.5 s.

Create and load a body for the animation object.

```
idx1 = h.createBody('pa24-250_orange.ac', 'Ac3d');
```

Load simulated flight trajectory data (`simdata`), located in `matlabroot\toolbox\astro\astdemos`.

```
load simdata;
```

Set the time series data for the body.

```
h.Bodies{1}.TimeSeriesSource = simdata;
```

Create a figure object for the animation object.

```
h.show();
```



Set up recording properties.

```
h.VideoRecord='on';  
h.VideoQuality = 50;  
h.VideoCompression = 'Motion JPEG AVI';  
h.VideoFilename = 'astMotion_JPEG';
```

Play the animation from `TFinal` to `TStart`.

```
h.TStart = 1;  
h.TFinal = 5;  
h.play();
```

Verify that a file named `astMotion_JPEG.avi` was created in the current folder. When you rerun the recording, notice that the play time is shorter than that in the previous example when you record for the length of the simulation time.

Disable recording to preserve the file.

```
h.VideoRecord = 'off';
```

Schedule Three Second Recording of Simulation

Schedule three second recording of animation object simulation.

Create an animation object.

```
h = Aero.Animation;
```

Control the frame display rate.

```
h.FramesPerSecond = 10;
```

Configure the animation object to set the seconds of animation data per second time-scaling (`TimeScaling`) property.

```
h.TimeScaling = 5;
```

The combination of `FramesPerSecond` and `TimeScaling` properties determines the time step of the simulation (`TimeScaling/|FramesPerSecond|`). These settings result in a time step of approximately 0.5 s.

Create and load a body for the animation object.

```
idx1 = h.createBody('pa24-250_orange.ac', 'Ac3d');
```

Load simulated flight trajectory data (`simdata`), located in `matlabroot\toolbox\ aero \astdemos`.

```
load simdata;
```

Set the time series data for the body.

```
h.Bodies{1}.TimeSeriesSource = simdata;
```

Create a figure object for the animation object.

```
h.show();
```


VideoTFinal property

Class: Aero.Animation

Package: Aero

Video recording stop time for scheduled recording

Values

Value between TStart and TFinal

Data type: double

Default: NaN, which uses the value of TFinal

Description

This property specifies the stop time of scheduled recording.

Use when VideoRecord is set to 'scheduled'. Use VideoTStart to set the start time of the recording.

VideoTStart property

Class: Aero.Animation

Package: Aero

Video recording start time for scheduled recording

Values

Value between TStart and TFinal

Data type: double

Default: NaN, which uses the value of TStart.

Description

This property specifies the start time of the scheduled recording.

Use when VideoRecord is set to 'scheduled'. Use VideoTFinal to set the end time of the recording.

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Importing from USAF Digital DATCOM Files

This example shows how to bring United States Air Force (USAF) Digital DATCOM files into the MATLAB® environment using the Aerospace Toolbox™ software.

Example USAF Digital DATCOM File

Here's a sample input file for USAF Digital DATCOM for a wing-body-horizontal tail-vertical tail configuration running over 5 alphas, 2 Mach numbers, and 2 altitudes and calculating static and dynamic derivatives:

```
type astdatcom.in
```

```
$FLTCON NMACH=2.0,MACH(1)=0.1,0.2$
$FLTCON NALT=2.0,ALT(1)=5000.0,8000.0$
$FLTCON NALPHA=5.,ALSCHD(1)=-2.0,0.0,2.0,
  ALSCHD(4)=4.0,8.0,LOOP=2.0$
$OPTINS SREF=225.8,CBARR=5.75,BLREF=41.15$
$SYNTHS XCG=7.08,ZCG=0.0,XW=6.1,ZW=-1.4,ALIW=1.1,XH=20.2,
  ZH=0.4,ALIH=0.0,XV=21.3,ZV=0.0,VERTUP=.TRUE.$
$BODY NX=10.0,
  X(1)=-4.9,0.0,3.0,6.1,9.1,13.3,20.2,23.5,25.9,
  R(1)=0.0,1.0,1.75,2.6,2.6,2.6,2.0,1.0,0.0$
$WGPLNF CHRDT=4.0,SSPNE=18.7,SSPN=20.6,CHRDR=7.2,SAVSI=0.0,CHSTAT=0.25,
  TWISTA=-1.1,SSPNDD=0.0,DHDADI=3.0,DHDADO=3.0,TYPE=1.0$
NACA-W-6-64A412
$HTPLNF CHRDT=2.3,SSPNE=5.7,SSPN=6.625,CHRDR=0.25,SAVSI=11.0,
  CHSTAT=1.0,TWISTA=0.0,TYPE=1.0$
NACA-H-4-0012
$VTPLNF CHRDT=2.7,SSPNE=5.0,SSPN=5.2,CHRDR=5.3,SAVSI=31.3,
  CHSTAT=0.25,TWISTA=0.0,TYPE=1.0$
NACA-V-4-0012
CASEID SKYHOGG BODY-WING-HORIZONTAL TAIL-VERTICAL TAIL CONFIG
DAMP
NEXT CASE
```

Here's the output file generated by USAF Digital DATCOM for the same wing-body-horizontal tail-vertical tail configuration running over 5 alphas, 2 Mach numbers, and 2 altitudes:

```
type astdatcom.out
```

```
THIS SOFTWARE AND ANY ACCOMPANYING DOCUMENTATION
IS RELEASED "AS IS". THE U.S. GOVERNMENT MAKES NO
WARRANTY OF ANY KIND, EXPRESS OR IMPLIED, CONCERNING
THIS SOFTWARE AND ANY ACCOMPANYING DOCUMENTATION,
INCLUDING, WITHOUT LIMITATION, ANY WARRANTIES OF
MERCHANTABILITY OR FITNESS FOR A PARTICULAR PURPOSE.
IN NO EVENT WILL THE U.S. GOVERNMENT BE LIABLE FOR ANY
DAMAGES, INCLUDING LOST PROFITS, LOST SAVINGS OR OTHER
INCIDENTAL OR CONSEQUENTIAL DAMAGES ARISING OUT OF THE
USE, OR INABILITY TO USE, THIS SOFTWARE OR ANY
ACCOMPANYING DOCUMENTATION, EVEN IF INFORMED IN ADVANCE
OF THE POSSIBILITY OF SUCH DAMAGES.
```

```
*****
*   USAF STABILITY AND CONTROL DIGITAL DATCOM   *
*   PROGRAM REV. JAN 96   DIRECT INQUIRIES TO:   *
*   WRIGHT LABORATORY (WL/FIGC)  ATTN: W. BLAKE  *
*   WRIGHT PATTERSON AFB, OHIO  45433           *
*   PHONE (513) 255-6764,   FAX (513) 258-4054  *
*****
```

```
1           CONERR - INPUT ERROR CHECKING
0 ERROR CODES - N* DENOTES THE NUMBER OF OCCURENCES OF EACH ERROR
0 A - UNKNOWN VARIABLE NAME
0 B - MISSING EQUAL SIGN FOLLOWING VARIABLE NAME
0 C - NON-ARRAY VARIABLE HAS AN ARRAY ELEMENT DESIGNATION - (N)
0 D - NON-ARRAY VARIABLE HAS MULTIPLE VALUES ASSIGNED
0 E - ASSIGNED VALUES EXCEED ARRAY DIMENSION
0 F - SYNTAX ERROR
```

```
0***** INPUT DATA CARDS *****
```

```
$FLTCON NMACH=2.0,MACH(1)=0.1,0.2$
$FLTCON NALT=2.0,ALT(1)=5000.0,8000.0$
$FLTCON NALPHA=5.,ALSCHD(1)=-2.0,0.0,2.0,
ALSCHD(4)=4.0,8.0,LOOP=2.0$
$OPTINS SREF=225.8,CBARR=5.75,BLREF=41.15$
$SYNTHS XCG=7.08,ZCG=0.0,XW=6.1,ZW=-1.4,ALIW=1.1,XH=20.2,
ZH=0.4,ALIH=0.0,XV=21.3,ZV=0.0,VERTUP=.TRUE.$
$BODY NX=10.0,
X(1)=-4.9,0.0,3.0,6.1,9.1,13.3,20.2,23.5,25.9,
R(1)=0.0,1.0,1.75,2.6,2.6,2.6,2.0,1.0,0.0$
$WGPLNF CHRDT=4.0,SSPNE=18.7,SSPN=20.6,CHRDR=7.2,SAVSI=0.0,CHSTAT=0.25,
TWISTA=-1.1,SSPNDD=0.0,DHDADI=3.0,DHDADO=3.0,TYPE=1.0$
NACA-W-6-64A412
$HTPLNF CHRDT=2.3,SSPNE=5.7,SSPN=6.625,CHRDR=0.25,SAVSI=11.0,
CHSTAT=1.0,TWISTA=0.0,TYPE=1.0$
NACA-H-4-0012
$VTPLNF CHRDT=2.7,SSPNE=5.0,SSPN=5.2,CHRDR=5.3,SAVSI=31.3,
CHSTAT=0.25,TWISTA=0.0,TYPE=1.0$
NACA-V-4-0012
CASEID SKYHOGG BODY-WING-HORIZONTAL TAIL-VERTICAL TAIL CONFIG
DAMP
NEXT CASE
```

```
1           THE FOLLOWING IS A LIST OF ALL INPUT CARDS FOR THIS CASE.
0
```

```
$FLTCON NMACH=2.0,MACH(1)=0.1,0.2$
$FLTCON NALT=2.0,ALT(1)=5000.0,8000.0$
$FLTCON NALPHA=5.,ALSCHD(1)=-2.0,0.0,2.0,
ALSCHD(4)=4.0,8.0,LOOP=2.0$
$OPTINS SREF=225.8,CBARR=5.75,BLREF=41.15$
$SYNTHS XCG=7.08,ZCG=0.0,XW=6.1,ZW=-1.4,ALIW=1.1,XH=20.2,
ZH=0.4,ALIH=0.0,XV=21.3,ZV=0.0,VERTUP=.TRUE.$
$BODY NX=10.0,
X(1)=-4.9,0.0,3.0,6.1,9.1,13.3,20.2,23.5,25.9,
R(1)=0.0,1.0,1.75,2.6,2.6,2.6,2.0,1.0,0.0$
```

```

$WGPLNF CHRDTP=4.0, SSPNE=18.7, SSPN=20.6, CHRDR=7.2, SAVSI=0.0, CHSTAT=0.25,
  TWISTA=-1.1, SSPNDD=0.0, DHDADI=3.0, DHDADO=3.0, TYPE=1.0$
NACA-W-6-64A412
$HTPLNF CHRDTP=2.3, SSPNE=5.7, SSPN=6.625, CHRDR=0.25, SAVSI=11.0,
  CHSTAT=1.0, TWISTA=0.0, TYPE=1.0$
NACA-H-4-0012
$VTPLNF CHRDTP=2.7, SSPNE=5.0, SSPN=5.2, CHRDR=5.3, SAVSI=31.3,
  CHSTAT=0.25, TWISTA=0.0, TYPE=1.0$
NACA-V-4-0012
CASEID SKYHOGG BODY-WING-HORIZONTAL TAIL-VERTICAL TAIL CONFIG
DAMP
NEXT CASE

```

0 INPUT DIMENSIONS ARE IN FT, SCALE FACTOR IS 1.0000

1 AUTOMATED STABILITY AND CONTROL METHODS PER APRIL 1976 VERSION OF I
WING SECTION DEFINITION

```

0 IDEAL ANGLE OF ATTACK = 0.00000 DEG.
ZERO LIFT ANGLE OF ATTACK = -3.09292 DEG.
IDEAL LIFT COEFFICIENT = 0.40000
ZERO LIFT PITCHING MOMENT COEFFICIENT = -0.08719
MACH ZERO LIFT-CURVE-SLOPE = 0.09654 /DEG.
LEADING EDGE RADIUS = 0.00993 FRACTION CHORD
MAXIMUM AIRFOIL THICKNESS = 0.12000 FRACTION CHORD
DELTA-Y = 2.46808 PERCENT CHORD

```

```

0 MACH= 0.1000 LIFT-CURVE-SLOPE = 0.09693 /DEG. XAC = 0.26404
0 MACH= 0.2000 LIFT-CURVE-SLOPE = 0.09811 /DEG. XAC = 0.26457

```

1 AUTOMATED STABILITY AND CONTROL METHODS PER APRIL 1976 VERSION OF I
HORIZONTAL TAIL SECTION DEFINITION

```

0 IDEAL ANGLE OF ATTACK = 0.00000 DEG.
ZERO LIFT ANGLE OF ATTACK = 0.00000 DEG.
IDEAL LIFT COEFFICIENT = 0.00000
ZERO LIFT PITCHING MOMENT COEFFICIENT = 0.00000
MACH ZERO LIFT-CURVE-SLOPE = 0.09596 /DEG.
LEADING EDGE RADIUS = 0.01587 FRACTION CHORD
MAXIMUM AIRFOIL THICKNESS = 0.12000 FRACTION CHORD
DELTA-Y = 3.16898 PERCENT CHORD

```

```

0 MACH= 0.1000 LIFT-CURVE-SLOPE = 0.09636 /DEG. XAC = 0.25854
0 MACH= 0.2000 LIFT-CURVE-SLOPE = 0.09761 /DEG. XAC = 0.25881

```

1 AUTOMATED STABILITY AND CONTROL METHODS PER APRIL 1976 VERSION OF I
VERTICAL TAIL SECTION DEFINITION

0 IDEAL ANGLE OF ATTACK = 0.00000 DEG.
 ZERO LIFT ANGLE OF ATTACK = 0.00000 DEG.
 IDEAL LIFT COEFFICIENT = 0.00000
 ZERO LIFT PITCHING MOMENT COEFFICIENT = 0.00000
 MACH ZERO LIFT-CURVE-SLOPE = 0.09596 /DEG.
 LEADING EDGE RADIUS = 0.01587 FRACTION CHORD
 MAXIMUM AIRFOIL THICKNESS = 0.12000 FRACTION CHORD
 DELTA-Y = 3.16898 PERCENT CHORD

0 MACH= 0.1000 LIFT-CURVE-SLOPE = 0.09636 /DEG. XAC = 0.25854
 0 MACH= 0.2000 LIFT-CURVE-SLOPE = 0.09761 /DEG. XAC = 0.25881
 1 AUTOMATED STABILITY AND CONTROL METHODS PER APRIL 1976 VERSION OF
 CHARACTERISTICS AT ANGLE OF ATTACK AND IN SIDESLIP
 WING-BODY-VERTICAL TAIL-HORIZONTAL TAIL CONFIGURATION
 SKYHOOGG BODY-WING-HORIZONTAL TAIL-VERTICAL TAIL CONFIG

----- FLIGHT CONDITIONS -----										
MACH	ALTITUDE	VELOCITY	PRESSURE	TEMPERATURE	REYNOLDS	REF.	REF.	-----		
NUMBER	FT	FT/SEC	LB/FT**2	DEG R	NUMBER	AREA	LONG	-----		
0 0.100	5000.00	109.70	1.7609E+03	500.843	6.1507E+05	225.800	5.75	-----		
0 ALPHA	CD	CL	CM	CN	CA	XCP	CLA	CMA	CY	
0	-2.0	0.032	0.113	-0.0340	0.112	0.035	-0.304	8.926E-02	-2.105E-02	-3.458
	0.0	0.035	0.296	-0.0752	0.296	0.035	-0.254	9.350E-02	-2.034E-02	
	2.0	0.042	0.487	-0.1153	0.488	0.025	-0.236	9.732E-02	-1.971E-02	
	4.0	0.052	0.685	-0.1541	0.687	0.004	-0.224	1.005E-01	-1.927E-02	
	8.0	0.084	1.098	-0.2304	1.099	-0.069	-0.210	1.059E-01	-1.890E-02	
0			ALPHA	Q/QINF	EPSLON	D(EPSLON)/D(ALPHA)				
0			-2.0	1.000	0.953	0.571				
			0.0	1.000	2.094	0.583				
			2.0	1.000	3.284	0.606				
			4.0	1.000	4.520	0.610				
			8.0	1.000	6.897	0.594				

1 AUTOMATED STABILITY AND CONTROL METHODS PER APRIL 1976 VERSION OF
 DYNAMIC DERIVATIVES
 WING-BODY-VERTICAL TAIL-HORIZONTAL TAIL CONFIGURATION
 SKYHOOGG BODY-WING-HORIZONTAL TAIL-VERTICAL TAIL CONFIG

----- FLIGHT CONDITIONS -----									
MACH	ALTITUDE	VELOCITY	PRESSURE	TEMPERATURE	REYNOLDS	REF.	REF.	-----	
NUMBER	FT	FT/SEC	LB/FT**2	DEG R	NUMBER	AREA	LONG	-----	
0 0.100	5000.00	109.70	1.7609E+03	500.843	6.1507E+05	225.800	5.75	-----	
0	DYNAMIC DERIVATIVES (PER DEGREE)								
0	-----PITCHING-----		-----ACCELERATION-----		-----ROLLING-----		-----		
0 ALPHA	CLQ	CMQ	CLAD	CMAD	CLP	CYP	CP	-----	
0								-----	

```

-2.00    9.739E-02   -8.918E-02    1.874E-02   -4.247E-02   -7.824E-03   -1.516E-03   -1.49
0.00     1.913E-02   -4.336E-02   -8.226E-03   -1.649E-03   -4.03
2.00     1.991E-02   -4.512E-02   -8.599E-03   -1.792E-03   -6.63
4.00     2.003E-02   -4.540E-02   -8.890E-03   -1.942E-03   -9.29
8.00     1.952E-02   -4.424E-02   -9.387E-03   -2.262E-03   -1.47
1
AUTOMATED STABILITY AND CONTROL METHODS PER APRIL 1976 VERSION OF
CHARACTERISTICS AT ANGLE OF ATTACK AND IN SIDESLIP
WING-BODY-VERTICAL TAIL-HORIZONTAL TAIL CONFIGURATION
SKYHOOGG BODY-WING-HORIZONTAL TAIL-VERTICAL TAIL CONFIG

```

```

----- FLIGHT CONDITIONS -----
MACH    ALTITUDE    VELOCITY    PRESSURE    TEMPERATURE    REYNOLDS    REF.    REFER
NUMBER    FT    FT/SEC    LB/FT**2    DEG R    NUMBER    AREA    LONG
0 0.200    5000.00    219.39    1.7609E+03    500.843    1.2301E+06    225.800    5.75
0
0 ALPHA    CD    CL    CM    CN    CA    XCP    CLA    CMA    CYP
0
-2.0    0.028    0.114    -0.0335    0.113    0.032    -0.297    9.000E-02    -2.124E-02    -3.465
0.0    0.031    0.298    -0.0751    0.298    0.031    -0.252    9.421E-02    -2.051E-02
2.0    0.038    0.491    -0.1155    0.492    0.021    -0.235    9.800E-02    -1.987E-02
4.0    0.048    0.690    -0.1546    0.692    0.000    -0.223    1.011E-01    -1.943E-02
8.0    0.081    1.105    -0.2316    1.106    -0.074    -0.209    1.065E-01    -1.906E-02
0
0
ALPHA    Q/QINF    EPSLON    D(EPSLON)/D(ALPHA)
-2.0    1.000    0.957    0.573
0.0    1.000    2.103    0.585
2.0    1.000    3.297    0.609
4.0    1.000    4.537    0.612
8.0    1.000    6.923    0.596
1
AUTOMATED STABILITY AND CONTROL METHODS PER APRIL 1976 VERSION OF
DYNAMIC DERIVATIVES
WING-BODY-VERTICAL TAIL-HORIZONTAL TAIL CONFIGURATION
SKYHOOGG BODY-WING-HORIZONTAL TAIL-VERTICAL TAIL CONFIG

```

```

----- FLIGHT CONDITIONS -----
MACH    ALTITUDE    VELOCITY    PRESSURE    TEMPERATURE    REYNOLDS    REF.    REFER
NUMBER    FT    FT/SEC    LB/FT**2    DEG R    NUMBER    AREA    LONG
0 0.200    5000.00    219.39    1.7609E+03    500.843    1.2301E+06    225.800    5.75
0
0
0 ALPHA    CLQ    CMQ    CLAD    CMAD    CLP    CYP    CIP
0
-2.00    9.840E-02   -8.993E-02    1.900E-02   -4.307E-02   -7.877E-03   -1.525E-03   -1.49
0.00     1.940E-02   -4.398E-02   -8.276E-03   -1.659E-03   -4.03
2.00     2.018E-02   -4.574E-02   -8.646E-03   -1.802E-03   -6.63
4.00     2.030E-02   -4.602E-02   -8.934E-03   -1.953E-03   -9.29
8.00     1.978E-02   -4.483E-02   -9.423E-03   -2.273E-03   -1.47
1
AUTOMATED STABILITY AND CONTROL METHODS PER APRIL 1976 VERSION OF
CHARACTERISTICS AT ANGLE OF ATTACK AND IN SIDESLIP
WING-BODY-VERTICAL TAIL-HORIZONTAL TAIL CONFIGURATION
SKYHOOGG BODY-WING-HORIZONTAL TAIL-VERTICAL TAIL CONFIG

```

```

----- FLIGHT CONDITIONS -----
MACH    ALTITUDE    VELOCITY    PRESSURE    TEMPERATURE    REYNOLDS    REF.    REFER
NUMBER    FT    FT/SEC    LB/FT**2    DEG R    NUMBER    AREA    LONG

```


0	0.100	8000.00	108.52	1.5721E+03	490.151	5.6457E+05	225.800	5.7		
0	ALPHA	CD	CL	CM	CN	CA	XCP	CLA	CMA	CY
0	-2.0	0.032	0.113	-0.0340	0.112	0.036	-0.305	8.926E-02	-2.106E-02	-3.458
	0.0	0.035	0.296	-0.0753	0.296	0.035	-0.254	9.350E-02	-2.034E-02	
	2.0	0.042	0.487	-0.1154	0.488	0.025	-0.236	9.732E-02	-1.971E-02	
	4.0	0.052	0.685	-0.1541	0.687	0.004	-0.224	1.005E-01	-1.927E-02	
	8.0	0.085	1.098	-0.2304	1.099	-0.069	-0.210	1.059E-01	-1.891E-02	

0				ALPHA	Q/QINF	EPSLON	D(EPSLON)/D(ALPHA)
0				-2.0	1.000	0.953	0.571
				0.0	1.000	2.094	0.583
				2.0	1.000	3.284	0.606
				4.0	1.000	4.520	0.610
				8.0	1.000	6.897	0.594

1 AUTOMATED STABILITY AND CONTROL METHODS PER APRIL 1976 VERSION OF
 DYNAMIC DERIVATIVES
 WING-BODY-VERTICAL TAIL-HORIZONTAL TAIL CONFIGURATION
 SKYHOOG BODY-WING-HORIZONTAL TAIL-VERTICAL TAIL CONFIG

FLIGHT CONDITIONS							
MACH NUMBER	ALTITUDE	VELOCITY	PRESSURE	TEMPERATURE	REYNOLDS NUMBER	REF. AREA	REFER. LONG. FT
0 0.100	8000.00	108.52	1.5721E+03	490.151	5.6457E+05	225.800	5.7

DYNAMIC DERIVATIVES (PER DEGREE)							
	PITCHING		ACCELERATION		ROLLING		
0	ALPHA	CLQ	CMQ	CLAD	CMAD	CLP	CYP
0	-2.00	9.739E-02	-8.918E-02	1.874E-02	-4.247E-02	-7.824E-03	-1.516E-03
	0.00			1.913E-02	-4.336E-02	-8.226E-03	-1.649E-03
	2.00			1.991E-02	-4.512E-02	-8.599E-03	-1.792E-03
	4.00			2.003E-02	-4.540E-02	-8.890E-03	-1.942E-03
	8.00			1.952E-02	-4.424E-02	-9.387E-03	-2.262E-03

1 AUTOMATED STABILITY AND CONTROL METHODS PER APRIL 1976 VERSION OF
 CHARACTERISTICS AT ANGLE OF ATTACK AND IN SIDESLIP
 WING-BODY-VERTICAL TAIL-HORIZONTAL TAIL CONFIGURATION
 SKYHOOG BODY-WING-HORIZONTAL TAIL-VERTICAL TAIL CONFIG

FLIGHT CONDITIONS							
MACH NUMBER	ALTITUDE	VELOCITY	PRESSURE	TEMPERATURE	REYNOLDS NUMBER	REF. AREA	REFER. LONG. FT
0 0.200	8000.00	217.04	1.5721E+03	490.151	1.1291E+06	225.800	5.7

DYNAMIC DERIVATIVE (PER DEGREE)										
0	ALPHA	CD	CL	CM	CN	CA	XCP	CLA	CMA	CY
0	-2.0	0.028	0.114	-0.0335	0.113	0.032	-0.297	9.000E-02	-2.124E-02	-3.465
	0.0	0.031	0.298	-0.0751	0.298	0.031	-0.252	9.421E-02	-2.051E-02	
	2.0	0.038	0.491	-0.1156	0.492	0.021	-0.235	9.800E-02	-1.987E-02	
	4.0	0.049	0.690	-0.1546	0.692	0.000	-0.223	1.011E-01	-1.943E-02	
	8.0	0.081	1.105	-0.2316	1.106	-0.073	-0.209	1.065E-01	-1.906E-02	

0				ALPHA	Q/QINF	EPSLON	D(EPSLON)/D(ALPHA)
0				-2.0	1.000	0.957	0.573
				0.0	1.000	2.103	0.585
				2.0	1.000	3.297	0.609

```

                                4.0      1.000      4.537      0.612
                                8.0      1.000      6.923      0.596
1  AUTOMATED STABILITY AND CONTROL METHODS PER APRIL 1976 VERSION OF
                                DYNAMIC DERIVATIVES
                                WING-BODY-VERTICAL TAIL-HORIZONTAL TAIL CONFIGURATION
                                SKYHOGG BODY-WING-HORIZONTAL TAIL-VERTICAL TAIL CONFIG

----- FLIGHT CONDITIONS -----
MACH      ALTITUDE    VELOCITY    PRESSURE    TEMPERATURE    REYNOLDS      REF.      REFER
NUMBER    FT            FT/SEC     LB/FT**2    DEG R          NUMBER        AREA      LONG
                                1/FT
0 0.200    8000.00      217.04     1.5721E+03  490.151       1.1291E+06   225.800  5.75
                                DYNAMIC DERIVATIVES (PER DEGREE)
0  -----PITCHING-----    -----ACCELERATION-----    -----ROLLING-----
0  ALPHA      CLQ      CMQ      CLAD      CMAD      CLP      CYP      CIP
0
    -2.00     9.840E-02  -8.993E-02  1.900E-02  -4.307E-02  -7.877E-03  -1.525E-03  -1.49
    0.00
    2.00
    4.00
    8.00
                                1.940E-02  -4.398E-02  -8.276E-03  -1.659E-03  -4.03
                                2.018E-02  -4.574E-02  -8.646E-03  -1.802E-03  -6.63
                                2.030E-02  -4.602E-02  -8.934E-03  -1.953E-03  -9.29
                                1.978E-02  -4.483E-02  -9.424E-03  -2.273E-03  -1.47
1  THE FOLLOWING IS A LIST OF ALL INPUT CARDS FOR THIS CASE.
0
1  END OF JOB.

```

Import Data from DATCOM Files

Use the `datcomimport` function to bring the Digital DATCOM data into MATLAB.

```
alldata = datcomimport('astdatcom.out', true, 0);
```

Examining Imported DATCOM Data

The `datcomimport` function creates a cell array of structures containing the data from the Digital DATCOM output file.

```
data = alldata{1}
```

```
data =
```

```
struct with fields:
```

```

    case: 'SKYHOGG BODY-WING-HORIZONTAL TAIL-VERTICAL TAIL CONFIG'
    mach: [0.1000 0.2000]
    alt: [5000 8000]
    alpha: [-2 0 2 4 8]
    nmach: 2
    nalt: 2
    nalpha: 5
    rnnub: []
    hypers: 0
    loop: 2
    sref: 225.8000
    cbar: 5.7500
    blref: 41.1500
    dim: 'ft'
    deriv: 'deg'

```

```
stmach: 0.6000
tsmach: 1.4000
save: 0
stype: []
trim: 0
damp: 1
build: 1
part: 0
highsym: 0
highasy: 0
highcon: 0
tjet: 0
hypeff: 0
lb: 0
pwr: 0
grnd: 0
wssp: 18.7000
hssp: 5.7000
ndelta: 0
delta: []
deltal: []
deltar: []
ngh: 0
grndht: []
config: [1x1 struct]
version: 1976
  cd: [5x2x2 double]
  cl: [5x2x2 double]
  cm: [5x2x2 double]
  cn: [5x2x2 double]
  ca: [5x2x2 double]
  xcp: [5x2x2 double]
  cma: [5x2x2 double]
  cyb: [5x2x2 double]
  cnb: [5x2x2 double]
  clb: [5x2x2 double]
  cla: [5x2x2 double]
  qqinf: [5x2x2 double]
  eps: [5x2x2 double]
  depsdalp: [5x2x2 double]
  clq: [5x2x2 double]
  cmq: [5x2x2 double]
  clad: [5x2x2 double]
  cmad: [5x2x2 double]
  clp: [5x2x2 double]
  cyp: [5x2x2 double]
  cnp: [5x2x2 double]
  cnr: [5x2x2 double]
  clr: [5x2x2 double]
```

Filling in Missing DATCOM Data

By default, missing data points are set to 99999 and data points are set to NaN where no DATCOM methods exist or where the method is not applicable.

It can be seen in the Digital DATCOM output file and examining the imported data that

C_{Yβ}, C_{nβ}, C_{Lq}, and C_{mq}

have data only in the first alpha value. Here are the imported data values.

`data.cyb`

`ans(:, :, 1) =`

```
1.0e+04 *
-0.0000 -0.0000
 9.9999  9.9999
 9.9999  9.9999
 9.9999  9.9999
 9.9999  9.9999
```

`ans(:, :, 2) =`

```
1.0e+04 *
-0.0000 -0.0000
 9.9999  9.9999
 9.9999  9.9999
 9.9999  9.9999
 9.9999  9.9999
```

`data.cnb`

`ans(:, :, 1) =`

```
1.0e+04 *
 0.0000  0.0000
 9.9999  9.9999
 9.9999  9.9999
 9.9999  9.9999
 9.9999  9.9999
```

`ans(:, :, 2) =`

```
1.0e+04 *
 0.0000  0.0000
 9.9999  9.9999
 9.9999  9.9999
 9.9999  9.9999
 9.9999  9.9999
```

`data.clq`

`ans(:, :, 1) =`

```

1.0e+04 *
    0.0000    0.0000
    9.9999    9.9999
    9.9999    9.9999
    9.9999    9.9999
    9.9999    9.9999

ans(:,:,2) =
    1.0e+04 *
    0.0000    0.0000
    9.9999    9.9999
    9.9999    9.9999
    9.9999    9.9999
    9.9999    9.9999
    
```

`data.cmq`

```

ans(:,:,1) =
    1.0e+04 *
   -0.0000   -0.0000
    9.9999    9.9999
    9.9999    9.9999
    9.9999    9.9999
    9.9999    9.9999

ans(:,:,2) =
    1.0e+04 *
   -0.0000   -0.0000
    9.9999    9.9999
    9.9999    9.9999
    9.9999    9.9999
    9.9999    9.9999
    
```

The missing data points will be filled with the values for the first alpha, since these data points are meant to be used for all alpha values.

```

aerotab = {'cyb' 'cnb' 'clq' 'cmq'};

for k = 1:length(aerotab)
    for m = 1:data.nmach
        for h = 1:data.nalt
            data.(aerotab{k})(:,m,h) = data.(aerotab{k})(1,m,h);
        end
    end
end
end
    
```

Here are the updated imported data values:

data.cyb

ans(:,:,1) =

```
-0.0035 -0.0035
-0.0035 -0.0035
-0.0035 -0.0035
-0.0035 -0.0035
-0.0035 -0.0035
```

ans(:,:,2) =

```
-0.0035 -0.0035
-0.0035 -0.0035
-0.0035 -0.0035
-0.0035 -0.0035
-0.0035 -0.0035
```

data.cnb

ans(:,:,1) =

```
1.0e-03 *
0.9142 0.8781
0.9142 0.8781
0.9142 0.8781
0.9142 0.8781
0.9142 0.8781
```

ans(:,:,2) =

```
1.0e-03 *
0.9190 0.8829
0.9190 0.8829
0.9190 0.8829
0.9190 0.8829
0.9190 0.8829
```

data.clq

ans(:,:,1) =

```
0.0974 0.0984
0.0974 0.0984
0.0974 0.0984
0.0974 0.0984
0.0974 0.0984
```

ans(:,:,2) =

```

0.0974    0.0984
0.0974    0.0984
0.0974    0.0984
0.0974    0.0984
0.0974    0.0984

```

```
data.cmq
```

```
ans(:,:,1) =
```

```

-0.0892    -0.0899
-0.0892    -0.0899
-0.0892    -0.0899
-0.0892    -0.0899
-0.0892    -0.0899

```

```
ans(:,:,2) =
```

```

-0.0892    -0.0899
-0.0892    -0.0899
-0.0892    -0.0899
-0.0892    -0.0899
-0.0892    -0.0899

```

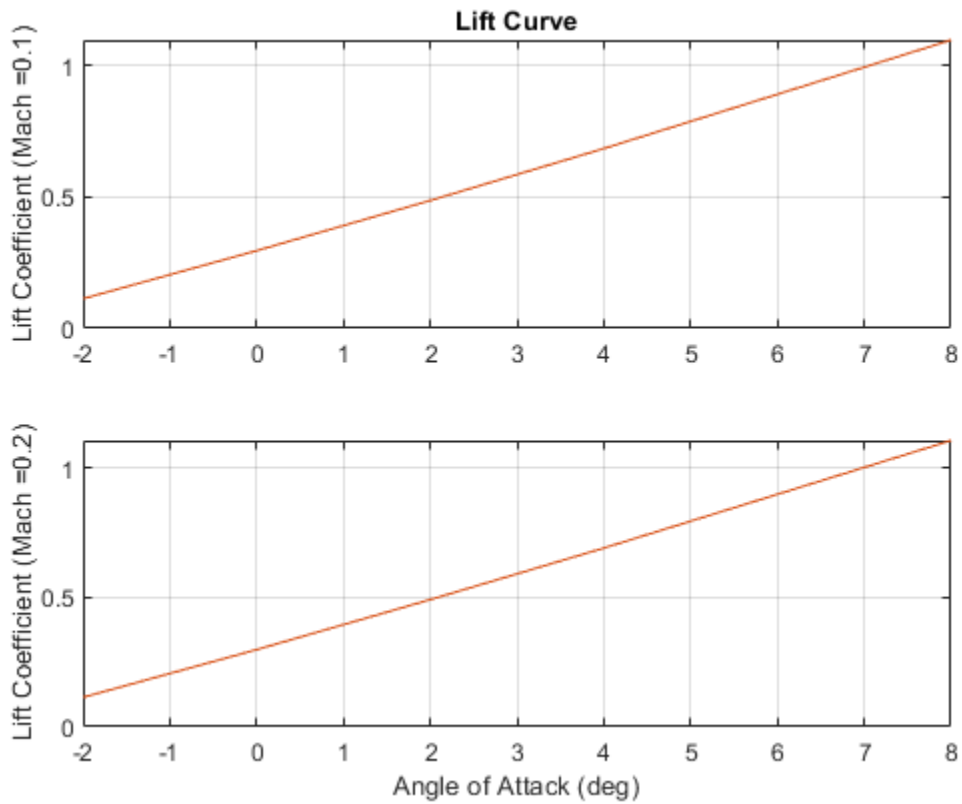
Plotting Aerodynamic Coefficients

Plot lift curve, drag polar and pitching moments.

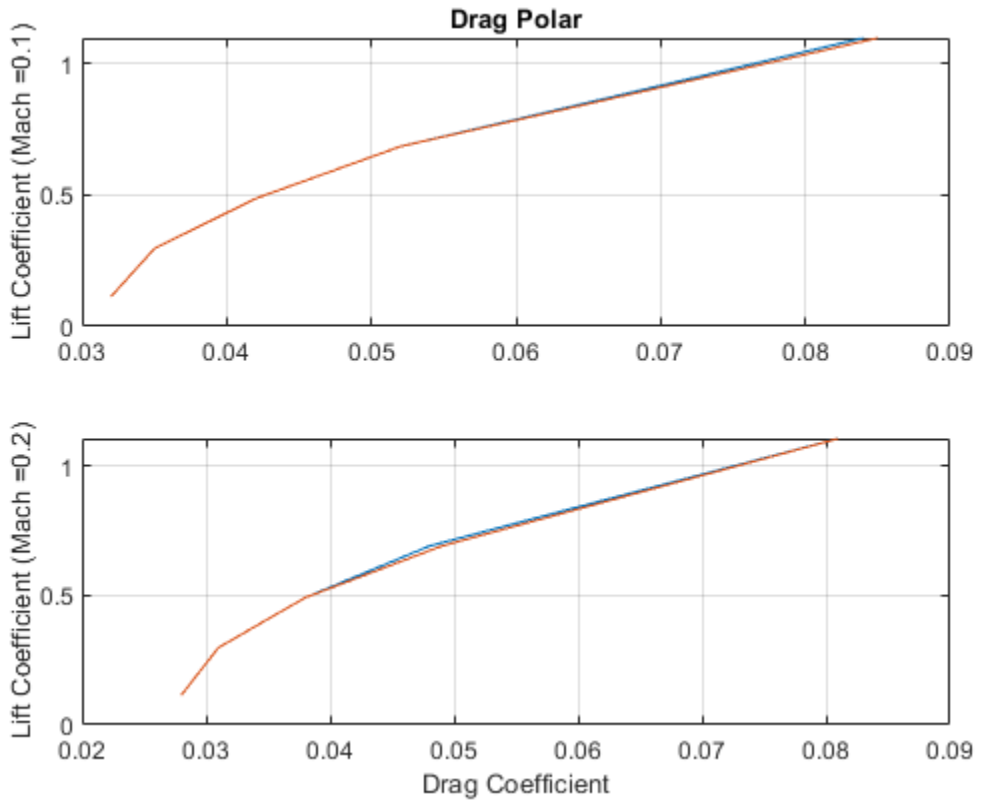
```

h1 = figure;
figtitle = {'Lift Curve' ''};
for k=1:2
    subplot(2,1,k)
    plot(data.alpha,permute(data.cl(:,k,:),[1 3 2]))
    grid
    ylabel(['Lift Coefficient (Mach = ' num2str(data.mach(k)) ' ')'])
    title(figtitle{k});
end
xlabel('Angle of Attack (deg)')

```

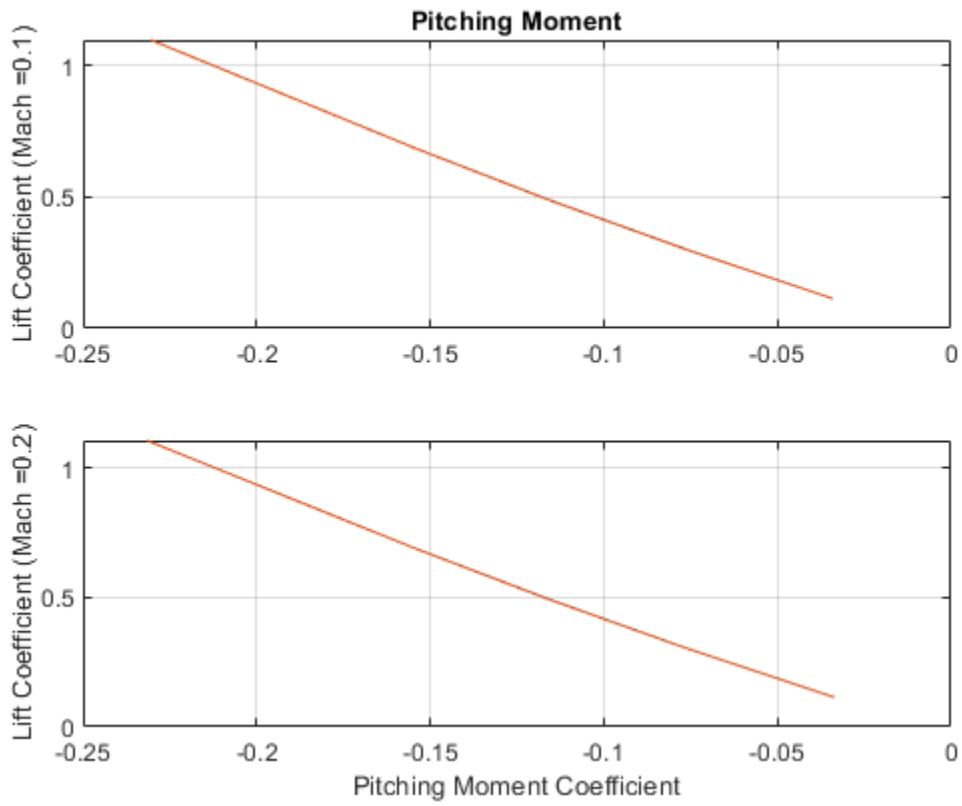


```
h2 = figure;
figtitle = {'Drag Polar' ''};
for k=1:2
    subplot(2,1,k)
    plot(permute(data.cd(:,k,:),[1 3 2]),permute(data.cl(:,k,:),[1 3 2]))
    grid
    ylabel(['Lift Coefficient (Mach =' num2str(data.mach(k)) ' ')])
    title(figtitle{k})
end
xlabel('Drag Coefficient')
```

```

h3 = figure;
figtitle = {'Pitching Moment' ''};
for k=1:2
    subplot(2,1,k)
    plot(permute(data.cm(:,k,:),[1 3 2]),permute(data.cl(:,k,:),[1 3 2]))
    grid
    ylabel(['Lift Coefficient (Mach = ' num2str(data.mach(k)) ' ')'])
    title(figtitle{k})
end
xlabel('Pitching Moment Coefficient')
    
```



```
close(h1,h2,h3);  
%#ok<*NOPTS>
```

Create a Flight Animation from Trajectory Data

This example shows how to create a flight animation for a trajectory using a FlightGear Animation object.

Note: When running this example within the product, you must customize the example with your FlightGear installation and uncomment the GenerateRunScript, system and play commands. You must also copy the \$MATLAB/toolbox/aero/astdemos/HL20 folder into the \$FLIGHTGEAR/data/Aircraft/ folder.

Load Recorded Flight Trajectory Data

The flight trajectory data for this example is stored in a comma separated value formatted file. Use **dlmread** to read the data from the file starting at row 1 and column 0 skipping the header information.

```
tdata = dlmread('asthl20log.csv', ',', 1, 0);
```

Create a Time Series Object from Trajectory Data

Use the MATLAB® **timeseries** command to create the time series object, ts, from the latitude, longitude, altitude, and Euler angle data along with the time array in tdata. To convert the latitude, longitude, and Euler angles from degrees to radians use the **convang** function.

```
ts = timeseries([convang(tdata(:, [3 2]), 'deg', 'rad') ...  
               tdata(:, 4) convang(tdata(:, 5:7), 'deg', 'rad')], tdata(:, 1));
```

You can create imported data from this data using other valid formats, such as 'Array6DoF', For example:

```
ts = [tdata(:, 1) convang(tdata(:, [3 2]), 'deg', 'rad') tdata(:, 4) ... convang(tdata(:, 5:7), 'deg', 'rad')];
```

and 'Array3DoF'.

```
ts = [tdata(:, 1) convang(tdata(:, 3), 'deg', 'rad') tdata(:, 4) ... convang(tdata(:, 6), 'deg', 'rad')];
```

Use FlightGearAnimation Object to Initialize Flight Animation

Open a FlightGearAnimation object.

```
h = Aero.FlightGearAnimation;
```

Set FlightGearAnimation object properties for timeseries.

```
h.TimeseriesSourceType = 'Timeseries';  
h.TimeseriesSource = ts;
```

Set FlightGearAnimation object properties about FlightGear

These properties include the path to the installation folder, the aircraft geometry model, and the network information for FlightGear flight simulator.

```
h.FlightGearBaseDirectory = 'C:\Program Files\FlightGear';  
h.GeometryModelName = 'HL20';  
h.DestinationIpAddress = '127.0.0.1';  
h.DestinationPort = '5502';
```

Set the desired initial conditions (location and orientation) for FlightGear flight simulator.

```
h.AirportId = 'KSF0';  
h.RunwayId = '10L';  
h.InitialAltitude = 7224;  
h.InitialHeading = 113;  
h.OffsetDistance = 4.72;  
h.OffsetAzimuth = 0;
```

Enable "just in time" scenery installation for FlightGear flight simulator. Required scenery will be downloaded while the simulator is running. For Windows® systems, you may encounter an error message while launching FlightGear with this option enabled. For more information, see "Installing Additional FlightGear Scenery" on page 2-42.

```
h.InstallScenery = true;
```

Disable FlightGear Shaders.

```
h.DisableShaders = true;
```

Set the seconds of animation data per second of wall-clock time.

```
h.TimeScaling = 5;
```

Use `get(h)` to check the FlightGearAnimation object properties and their values.

`get(h)`

```
TimeseriesSource: [1x1 timeseries]  
TimeseriesSourceType: 'Timeseries'  
TimeseriesReadFcn: @TimeseriesRead  
TimeScaling: 5  
FramesPerSecond: 12  
OutputFileName: 'runfg.bat'  
FlightGearBaseDirectory: 'C:\Program Files\FlightGear'  
GeometryModelName: 'HL20'  
DestinationIpAddress: '127.0.0.1'  
DestinationPort: '5502'  
AirportId: 'KSF0'  
RunwayId: '10L'  
InitialAltitude: 7224  
InitialHeading: 113  
OffsetDistance: 4.7200  
OffsetAzimuth: 0  
InstallScenery: 1  
DisableShaders: 1  
TStart: NaN  
TFinal: NaN  
Architecture: 'Default'
```

Create a Run Script to Launch FlightGear Flight Simulator

To start FlightGear with the desired initial conditions (location, date, time, weather, and operating modes), create a run script with the **GenerateRunScript** command. By default, **GenerateRunScript** saves the run script as a text file named 'runfg.bat'.

`GenerateRunScript(h)`

You do not need to generate this file each time the data is viewed. Generate it only when the desired initial conditions or FlightGear information changes.

Start FlightGear Flight Simulator

To start FlightGear from the MATLAB command prompt, type the **system** command to execute the run script created by **GenerateRunScript**.

```
system('runfg.bat &');
```

Tip: With the FlightGear window in focus, press the V key to alternate between the different aircraft views: cockpit view, helicopter view, and chase view.

Play the Flight Animation of Trajectory Data

Once FlightGear is up and running, the FlightGearAnimation object can start to communicate with FlightGear. To display the flight animation with FlightGear, use the **play** command.

```
play(h)
```

To display a screenshot of the flight animation, use the MATLAB **image** command.

```
image(imread([matlabroot filesep fullfile('toolbox','aero','astdemos','figures','astfganim01.png')  
axis off;  
set(gca,'Position',[ 0 0 1 1 ]);  
set(gcf,'MenuBar','none');
```



Estimating G Forces for Flight Data

This example shows how to load flight data and estimate G forces during the flight.

Load Recorded Flight Data for Analysis

The recorded data contains the following flight parameters:

- angle of attack (alpha) in radians,
- sideslip angle (beta) in radians,
- indicated airspeed (IAS) in knots,
- body angular rates (omega) in radians/second,
- downrange and crossrange positions in feet, and
- altitude (alt) in feet.

```
load('astflight.mat');
```

Extract Flight Parameters from Loaded Data

MATLAB® variables are created for angle of attack (alpha), sideslip angle (beta), body angular rates (omega), and altitude (alt) from recorded data. The `convangvel` function is used to convert body angular rates from radians per second (rad/s) to degrees per second (deg/s).

```
alpha = fltdata(:,2);  
beta = fltdata(:,3);  
omega = convangvel( fltdata(:,5:7), 'rad/s', 'deg/s' );  
alt = fltdata(:,10);
```

Compute True Airspeed from Indicated Airspeed

In this set of flight data, indicated airspeed (IAS) was recorded. Indicated airspeed (IAS) is displayed in the cockpit instrumentation. To perform calculations, true airspeed (TAS), the airspeed without measurement errors, is typically used.

Measurement errors are introduced through the pitot-static airspeed indicators used to determine airspeed. These measurement errors are *density error*, *compressibility error* and *calibration error*. Applying these errors to true airspeed results in indicated airspeed.

- *Density error* occurs due to lower air density at altitude. The effect is an airspeed indicator reads lower than true airspeed at higher altitudes. When the difference or error in air density at altitude from air density on a standard day at sea level is applied to true airspeed, it results in equivalent airspeed (EAS). Equivalent airspeed is true airspeed modified with the changes in atmospheric density which affect the airspeed indicator.
- *Compressibility error* occurs because air has a limited ability to resist compression. This ability is reduced by an increase in altitude, an increase in speed, or a restricted volume. Within the airspeed indicator, there is a certain amount of trapped air. When flying at high altitudes and higher airspeeds, calibrated airspeed (CAS) is always higher than equivalent airspeed. Calibrated airspeed is equivalent airspeed modified with compressibility effects of air which affect the airspeed indicator.
- *Calibration error* is specific to a given aircraft design. Calibration error is the result of the position and placement of the static vent(s) to maintain a pressure equal to atmospheric pressure inside the airspeed indicator. Position and placement of the static vent along with angle of attack and

velocity of the aircraft will determine the pressure inside the airspeed indicator and thus the amount of calibration error of the airspeed indicator. A calibration table is usually given in the pilot operating handbook (POH) or in other aircraft specifications. Using this calibration table, the indicated airspeed (IAS) is determined from calibrated airspeed by modifying it with calibration error of the airspeed indicator.

The following data is the airspeed calibration table for the airspeed indicator of the aircraft with zero flap deflection. The airspeed calibration table converts indicated airspeed (IAS) to calibrated airspeed (CAS) by removing the calibration error.

```
flaps0IAS = 40:10:140;
flaps0CAS = [43 51 59 68 77 87 98 108 118 129 140];
```

The indicated airspeed (IAS) from the flight and airspeed calibration table are used to determine the calibrated airspeed (CAS) for the flight.

```
CAS = interp1( flaps0IAS, flaps0CAS, fltdata(:,4) );
```

The atmospheric properties, temperature (T), speed of sound (a), pressure (P), and density (rho), are determined at altitude for standard day using the `atmoscoesa` function.

```
[T, a, P, rho]= atmoscoesa( alt );
```

Once the calibrated airspeed (CAS) and the atmospheric properties are determined, the true airspeed (Vt) can be calculated using the `correctairspeed` function.

```
Vt = correctairspeed( CAS, a, P, 'CAS', 'TAS' );
```

Import Digital DATCOM Data for Aircraft

Use the `datcomimport` function to bring the Digital DATCOM data into MATLAB. The units for this aerodynamic information are feet and degrees.

```
data = datcomimport( 'astflight.out', true, 0 );
```

It can be seen in the Digital DATCOM output file and examining the imported data that

$C_{Y\beta}$, $C_{n\beta}$, C_{lq} , and C_{mq}

have data only in the first alpha value. By default, missing data points are set to 99999. The missing data points are filled with the values for the first alpha, since these data points are meant to be used for all alpha values.

```
aerotab = {'cyb' 'cnb' 'clq' 'cmq'};
for k = 1:length(aerotab)
    for m = 1:data{1}.nmach
        for h = 1:data{1}.nalt
            data{1}.(aerotab{k})(:,m,h) = data{1}.(aerotab{k})(1,m,h);
        end
    end
end
```

Interpolate Stability and Dynamic Derivatives at Flight Conditions

The stability and dynamic derivatives in the digital DATCOM structure are 3-D tables which are functions of Mach number, angle of attack in degrees, and altitude in feet. In order to perform 3-D

linear interpolation (`interp3`), the indices for the derivative tables are required to be monotonic and plaid. Indices of this form are generated by the `meshgrid` function.

```
[mnum, alp, h] = meshgrid( data{1}.mach, data{1}.alpha, data{1}.alt );
```

Since the angular units of the derivatives are in degrees, the units of angle of attack (`alpha`) are converted from radians from degrees by the function `convang`.

```
alphadeg = convang( alpha, 'rad', 'deg' );
```

The Mach numbers for the flight are calculated by the function `machnumber` using speed of sound (`a`) and airspeed (`Vt`).

```
Mach = machnumber( convvel( [Vt zeros(size(Vt,1),2)], 'kts', 'm/s' ), a );
```

Looping through the flight conditions, allows `interp3` to be used to linearly interpolate derivative tables to find static and dynamic derivatives at those flight conditions.

```
for k = length(alt):-1:1
    cd(k,:) = interp3( mnum, alp, h, data{1}.cd, Mach(k), alphadeg(k), alt(k), 'linear');
    cyb(k,:) = interp3( mnum, alp, h, data{1}.cyb, Mach(k), alphadeg(k), alt(k), 'linear');
    cl(k,:) = interp3( mnum, alp, h, data{1}.cl, Mach(k), alphadeg(k), alt(k), 'linear');
    cyp(k,:) = interp3( mnum, alp, h, data{1}.cyp, Mach(k), alphadeg(k), alt(k), 'linear');
    clad(k,:) = interp3( mnum, alp, h, data{1}.clad, Mach(k), alphadeg(k), alt(k), 'linear');
end
```

Compute Aerodynamic Coefficients

Once the derivatives are found for the flight conditions, aerodynamic coefficients can be calculated.

Reference lengths and areas used in the aerodynamic coefficient computation are extracted from the digital DATCOM structure.

```
cbar = data{1}.cbar;
Sref = data{1}.sref;
bref = data{1}.blref;
```

The angular units of the derivatives are in degrees, so the units of sideslip angle (`beta`) are converted from radians from degrees by the function `convang`.

```
betadeg = convang( beta, 'rad', 'deg' );
```

In order to calculate the aerodynamic coefficients, the body angular rates (`omega`) need to be given in the stability axes, like the derivatives. The function `dcmbody2wind` generates the direction cosine matrix for body axes to stability axes (`Tsb`) when the sideslip angle (`beta`) is set to zero.

```
Tsb = dcmbody2wind( alpha, zeros(size(alpha)) );
```

The rate of change in angle of attack (`alpha_dot`) is also needed to find angular rates in stability axis (`omega_stab`). The function `diff` is used on `alpha` in degrees divided by data sample time (0.50 seconds) to approximate the rate of change in angle of attack (`alpha_dot`).

```
alpha_dot = diff( alphadeg/0.50 );
```

The last value of `alpha_dot` is held to keep the length of `alpha_dot` consistent with other arrays in this calculation. This is needed because the `diff` function returns an array that is one value shorter than the input


```
alpha_dot = [alpha_dot; alpha_dot(end)];
```

The angular rates in stability axis (omega_stab) are computed for the flight data. The angular rates are reshaped into a 3-D matrix to be multiplied with the 3-D matrix for the direction cosine matrix for body axes to stability axes (Tsb).

```
omega_temp = reshape((omega - [zeros(size(alpha)) alpha_dot zeros(size(alpha))])',3,1,length(omega));
for k = length(omega):-1:1
    omega_stab(k,:) = (Tsb(:,:,k)*omega_temp(:,:,k))';
end
```

Compute the drag coefficient (CD), the side force coefficient (CY) and the lift coefficient (CL). The convvel function is used to get the units of airspeed (Vt) consistent with those of the derivatives.

```
CD = cd;
CY = cyb.*betadeg + cyp.*omega_stab(:,1)*bref/2./convvel(Vt, 'kts', 'ft/s');
CL = cl + clad.*alpha_dot*cbar/2./convvel(Vt, 'kts', 'ft/s');
```

Compute Forces

Aerodynamic coefficients for drag, side force and lift are used to compute aerodynamic forces.

Dynamic pressure is needed to calculate the aerodynamic forces. The function dpressure compute dynamic pressure from the airspeed (Vt) and density (rho). The convvel function is used to get the units of airspeed (Vt) consistent with those of density (rho).

```
qbar = dpressure( convvel( [Vt zeros(size(Vt,1),2)], 'kts', 'm/s' ), rho );
```

To find forces in body axes, the direction cosine matrix for stability axes to body axes (Tbs) is needed. Direction cosine matrix for stability axes to body axes (Tbs) is the transpose of direction cosine matrix for body axes to stability axes (Tsb). To take the transpose of a 3-D array, the permute function is used.

```
Tbs = permute( Tsb, [2 1 3] );
```

Looping through the flight data points, aerodynamic forces are computed and converted from stability to body axes. The convpres function is used to get the units of dynamic pressure (qbar) consistent with those of the reference area (Sref).

```
for k = length(qbar):-1:1
    forces_lbs(k,:) = Tbs(:,:,k)*(convpres(qbar(k), 'Pa', 'psf')*Sref*[-CD(k); CY(k); -CL(k)]);
end
```

A constant thrust is estimated in the body axes.

```
thrust = ones(length(forces_lbs),1)*[200 0 0];
```

The constant thrust estimate is added to aerodynamic forces and units are converted to metric.

```
forces = convforce((forces_lbs + thrust), 'lbf', 'N');
```

Estimate G Forces

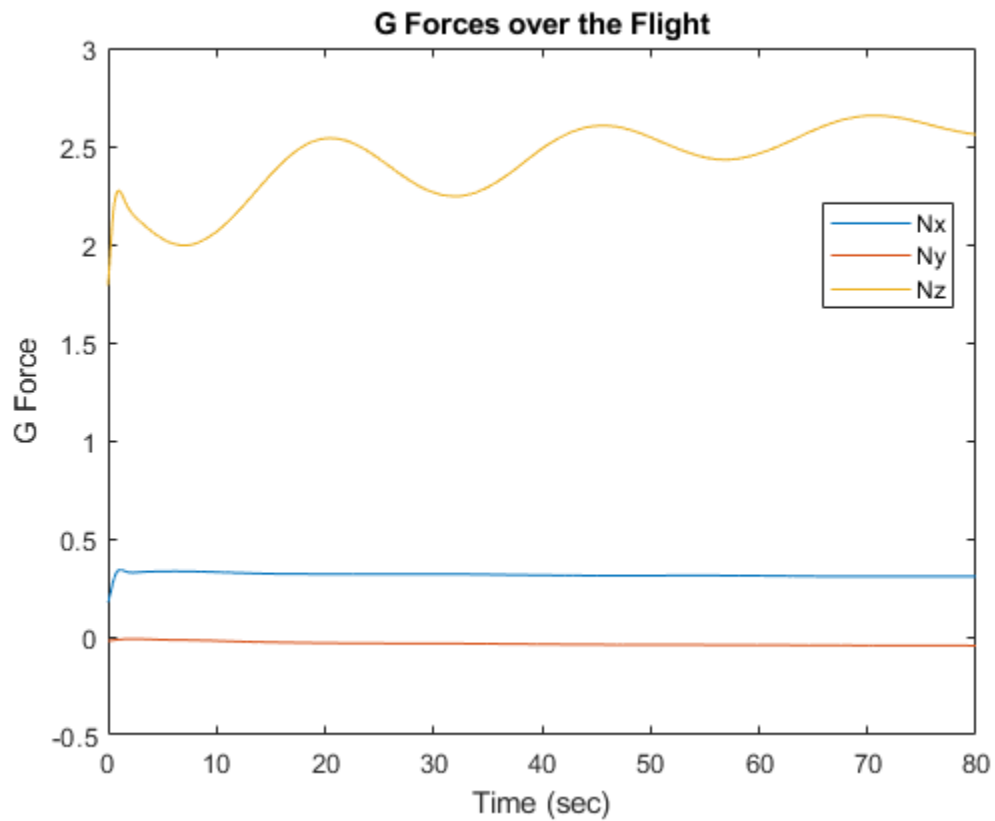
Using the calculated forces, estimate G forces during the flight.

Accelerations are estimated using the calculated forces and mass converted into kilograms using convmass. Accelerations are converted to G forces using convacc.

```
N = convacc( ( forces/convmass(84.2, 'slug', 'kg') ), 'm/s^2', 'G's');  
N = [N(:,1:2) -N(:,3)];
```

G forces are plotted over the flight.

```
h1 = figure;  
plot(fldata(:,1), N);  
xlabel('Time (sec)')  
ylabel('G Force')  
title('G Forces over the Flight')  
legend('Nx', 'Ny', 'Nz', 'Location', 'Best')
```



```
close(h1);
```

Calculating Best Glide Quantities

This example shows how to perform glide calculations for a Cessna 172 following Example 9.1 in Reference 1 using the Aerospace Toolbox™ software.

Best glide calculations provide values (velocity and glide angle) that minimize drag and maximize lift-drag ratio (also called the glide ratio).

Aircraft Specifications

The aircraft parameters are declared as follows.

```
W = 2400; % weight, lbf
S = 174; % wing reference area, ft^2;
A = 7.38; % wing aspect ratio
C_D0 = 0.037; % flaps up parasite drag coefficient
e = 0.72; % airplane efficiency factor
```

Conditions

Set the current aircraft conditions. The bank angle (phi) is zero for this case.

```
h = 4000; % altitude, ft
phi = 0; % bank angle, deg
```

Convert altitude to meters using `convlength`. The atmospheric calculations in the next step require values in metric units.

```
h_m = convlength(h, 'ft', 'm');
```

Calculate atmospheric parameters based on altitude using `atmoscoesa`:

```
[T, a, P, rho] = atmoscoesa(h_m, 'Warning');
```

Convert density from metric to English units using `convdensity`:

```
rho = convdensity(rho, 'kg/m^3', 'slug/ft^3');
```

Best Glide Data

Best glide velocity is calculated using the following equation. TAS (true airspeed in feet per second) is the velocity of the aircraft relative to the surrounding air mass.

$$TAS_{bg} = \sqrt{\frac{2W}{\rho S}} \times \left[\frac{1}{4C_{D_0}^2 + C_{D_0}\pi e A \cos^2 \phi} \right]^{\frac{1}{4}}$$

```
TAS_bg = sqrt((2*W) / (rho*S))...
*(1./(4*C_D0.^2 + C_D0.*pi*e*A*cos(phi)^2)).^(1/4); % TAS, fps
```

Convert velocity from fps to kts using `convvel`. KTAS is true airspeed in knots.

```
KTAS_bg = convvel(TAS_bg, 'ft/s', 'kts');
```

Convert KTAS to KCAS using `correctairspeed`. KCAS (calibrated airspeed in knots) is the velocity corrected for instrument error and position error. This position error comes from inaccuracies in static pressure measurements at different points in the flight envelope.

```
KCAS_bg = correctairspeed(KTAS_bg,a,P, 'TAS', 'CAS');
```

Best glide angle is calculated using:

$$\sin \gamma_{bg} = -\sqrt{\frac{4C_{D_0}}{\pi e A \cos^2 \phi + 4C_{D_0}}}$$

This is the angle between the flight path and the ground that provides the highest L/D ratio.

```
gamma_bg_rad = asin( -sqrt((4.*C_D0')./(pi*e*A*cos(phi)^2 + 4.*C_D0')) );
```

Convert glide angle from radians to degrees using convang:

```
gamma_bg = convang(gamma_bg_rad, 'rad', 'deg');
```

Best glide drag is calculated using:

$$D_{min} = D_{bg} = \frac{1}{2} \rho (TAS_{bg}^2) S (2C_{D_0}) = -W \sin \gamma_{bg}$$

```
D_bg = -W*sin(gamma_bg_rad);
```

Best glide lift is calculated using:

$$L_{bg} = L_{max} = W \cos \gamma_{bg} = \sqrt{W^2 - D_{bg}^2}$$

```
L_bg = W*cos(gamma_bg_rad);
```

Calculate dynamic pressure using dpressure:

```
qbar = dpressure([TAS_bg' zeros(size(TAS_bg,2),2)], rho);
```

Calculate drag and lift coefficients using:

$$C_{D_{bg}} = \frac{D_{bg}}{\bar{q}S}$$

$$C_{L_{bg}} = \frac{L_{bg}}{\bar{q}S}$$

```
C_D_bg = D_bg./(qbar*S);
```

```
C_L_bg = L_bg./(qbar*S);
```

Summary of Best Glide Values

Here are the best glide values:

$$KCAS_{bg} = 71.9 KCAS$$

$$\gamma_{bg} = -5.38 \text{ deg}$$

$$C_{D_{bg}} = 0.074$$

$$C_{L_{bg}} = 0.7859$$

$$D_{bg} = 224.9\text{ lbf}$$

$$L_{bg} = 2389.4\text{ lbf}$$

Verification

These plots show drag and lift-drag ratio plots for the aircraft as a function of KCAS. The plots are used to verify the best glide calculations.

Set range of airspeeds and convert to KCAS using `convvel` and `correctairspeed`:

```
TAS = (70:200)'; % true airspeed, fps
KTAS = convvel(TAS,'ft/s','kts')'; % true airspeed, kts
KCAS = correctairspeed(KTAS,a,P,'TAS','CAS')'; % corrected airspeed, kts
```

Calculate dynamic pressure for new airspeeds using `dpressure`:

```
qbar = dpressure([TAS zeros(size(TAS,1),2)], rho);
```

Calculate parasite drag using:

$$D_p = \frac{1}{2} \rho S C_{D_0} (TAS^2)$$

```
Dp = qbar*S.*C_D0;
```

Calculate induced drag using:

$$D_i = \frac{2W^2}{\rho S \pi e A} \frac{1}{(TAS^2)}$$

```
Di = (2*W^2)/(rho*S*pi*e*A).*(TAS.^-2);
```

Calculate total drag using:

$$D = D_p + D_i$$

```
D = Dp + Di;
```

Approximate lift as weight (assuming small glide angle and small angle of attack). At this speed, assuming

$$C_L = 2\pi\alpha$$

and using

$$C_{L_{bg}}$$

from above, the angle of attack is about 7 degrees. Adding the flight path angle (i.e. best glide angle) from above shows the fuselage pitch (attitude angle θ) to be about 2 degrees.

```
L = W;
```

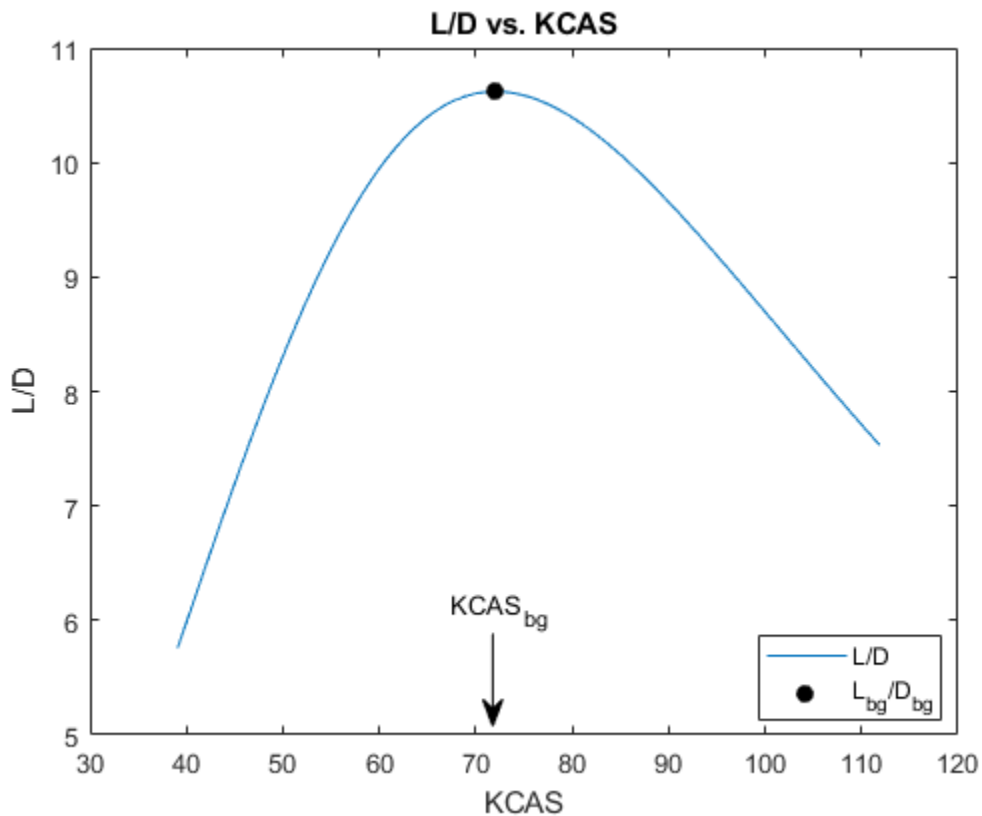
Plot L/D versus KCAS

As expected, the maximum L/D occurs at approximately the best glide velocity calculated above.

```

h1 = figure;
plot(KCAS,L./D);
title('L/D vs. KCAS');
xlabel('KCAS'); ylabel('L/D');
hold on
plot(KCAS_bg,L_bg/D_bg,'Marker','o','MarkerFaceColor','black',...
     'MarkerEdgeColor','black','Color','white');
hold off
legend('L/D','L_{bg}/D_{bg}','Location','Best');
annotation('textarrow',[0.49 0.49],[0.23 0.12],'String','KCAS_{bg}');

```



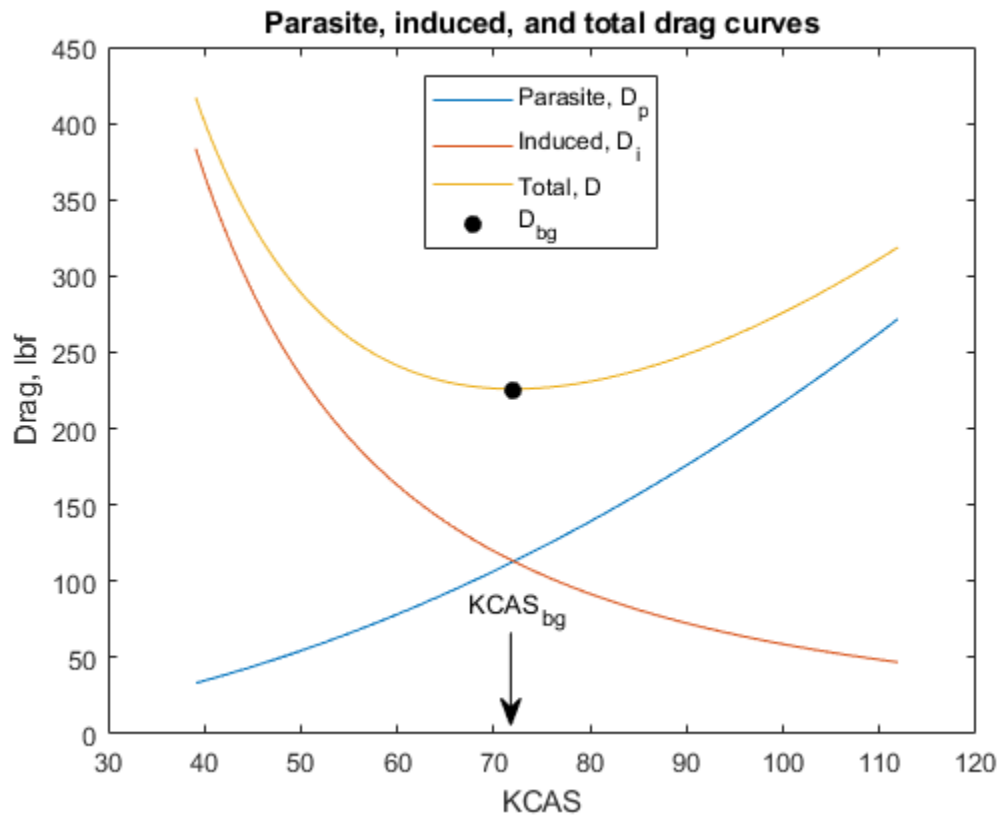
Plot parasite, induced, and total drag curves

Notice the minimum total drag (i.e. D_{bg}) occurs at approximately the same best glide velocity calculated above.

```

h2 = figure;
plot(KCAS,Dp,KCAS,Di,KCAS,D);
title('Parasite, induced, and total drag curves');
xlabel('KCAS'); ylabel('Drag, lbf');
hold on
plot(KCAS_bg,D_bg,'Marker','o','MarkerFaceColor','black',...
     'MarkerEdgeColor','black','Color','white');
hold off
legend('Parasite, D_p','Induced, D_i','Total, D','D_{bg}','Location','Best');
annotation('textarrow',[0.49 0.49],[0.23 0.12],'String','KCAS_{bg}');

```



close(h1,h2);

Reference

- [1] Lowry, J. T., "Performance of Light Aircraft", AIAA(R) Education Series, Washington, DC, 1999.

Overlaying Simulated and Actual Flight Data

This example shows how to visualize simulated versus actual flight trajectories with the animation object (`Aero.Animation`) while showing some of the animation object functionality. In this example, you can use the `Aero.Animation` object to create and configure an animation object, then use that object to create, visualize, and manipulate bodies for the flight trajectories.

Create the Animation Object

This code creates an instance of the `Aero.Animation` object.

```
h = Aero.Animation;
```

Set the Animation Object Properties

This code sets the number of frames per second. This controls the rate at which frames are displayed in the figure window.

```
h.FramesPerSecond = 10;
```

This code sets the seconds of animation data per second time scaling. This property and the `'FramesPerSecond'` property determine the time step of the simulation. The settings in this example result in a time step of approximately 0.5s. The equation is $(1/\text{FramesPerSecond}) * \text{TimeScaling}$ along with some extra terms to handle for sub-second precision.

```
h.TimeScaling = 5;
```

Create and Load Bodies

This code loads the bodies using `createBody` for the animation object, `h`. This example will use these bodies to work with and display the simulated and actual flight trajectories. The first body is orange and will represent simulated data. The second body is blue and will represent the actual flight data.

```
idx1 = h.createBody('pa24-250_orange.ac', 'Ac3d');
idx2 = h.createBody('pa24-250_blue.ac', 'Ac3d');
```

Load Recorded Data for Flight Trajectories

Using the bodies from the previous code, this code provides simulated and actual recorded data for flight trajectories in the following files:

- The `simdata` file contains logged simulated data. `simdata` is set up as a 6DoF array, which is one of the default data formats.
- The `fltdata` file contains actual flight test data. In this example, `fltdata` is set up in a custom format. The example must create a custom read function and set the `'TimeSeriesSourceType'` parameter to `'Custom'`.

To load the `simdata` and `fltdata` files:

```
load simdata
load fltdata
```

To work with the custom flight test data, this code sets the second body `'TimeSeriesReadFcn'`. The custom read function is located here: `matlabroot/toolbox/aero/astdemos/CustomReadBodyTSData.m`


```
h.Bodies{2}.TimeseriesReadFcn = @CustomReadBodyTSData;
```

Set the bodies' timeseries data.

```
h.Bodies{1}.TimeSeriesSource = simdata;  
h.Bodies{2}.TimeSeriesSource = fltdata;  
h.Bodies{2}.TimeSeriesSourceType = 'Custom';
```

Camera Manipulation

This code illustrates how you can manipulate the camera for the two bodies.

The 'PositionFcn' property of a camera object controls the camera position relative to the bodies in the animation. The default camera 'PositionFcn' follows the path of a first order chase vehicle. Therefore, it takes a few steps for the camera to position itself correctly in the chase plane position. The default 'PositionFcn' is located here: `matlabroot/toolbox/aero/aero/doFirstOrderChaseCameraDynamics.m`

Set 'PositionFcn'.

```
h.Camera.PositionFcn = @doFirstOrderChaseCameraDynamics;
```

Display Body Geometries in Figure

This code uses the show method to create the figure graphics object for the animation object.

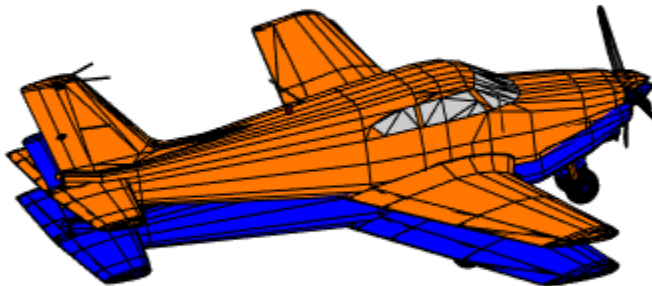
```
h.show();
```



Use the Animation Object to Play Back Flight Trajectories

This code uses the `play` method to animate bodies for the duration of the timeseries data. Using this method will illustrate the slight differences between the simulated and flight data.

```
h.play();
```



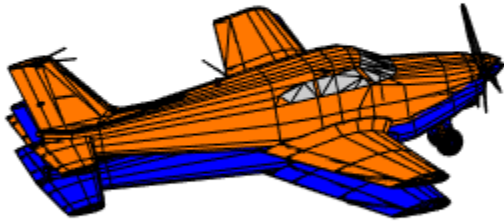
The code can also use a custom, simplified 'PositionFcn' that is a static position based on the position of the bodies (i.e., no dynamics). The simplified 'PositionFcn' is located here: `matlabroot/toolbox/aero/astdemos/staticCameraPosition.m`

Set the new 'PositionFcn'.

```
h.Camera.PositionFcn = @staticCameraPosition;
```

Run the animation with new 'PositionFcn'.

```
h.play();
```



Move Bodies

This code illustrates how to move the bodies to the starting position (based on timeseries data) and update the camera position according to the new 'PositionFcn'. This code uses `updateBodies` and `updateCamera`.

```
t = 0;  
h.updateBodies(t);  
h.updateCamera(t);
```



Reposition Bodies

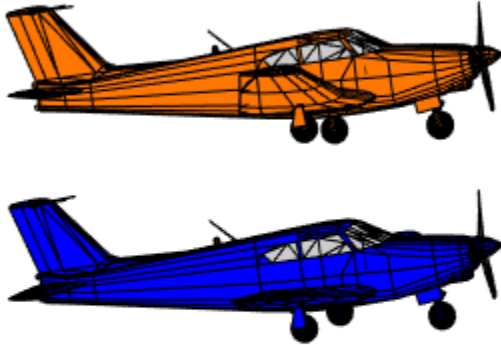
This code illustrates how to reposition the bodies by first getting the current body position and then separating the bodies.

Get current body positions and rotations from the body objects.

```
pos1 = h.Bodies{1}.Position;  
rot1 = h.Bodies{1}.Rotation;  
pos2 = h.Bodies{2}.Position;  
rot2 = h.Bodies{2}.Rotation;
```

Separate bodies using `moveBody`. This code separates and repositions the two bodies.

```
h.moveBody(1,pos1 + [0 0 -3],rot1);  
h.moveBody(2,pos1 + [0 0 0],rot2);
```



Create Transparency in the First Body

This code illustrates how to create transparency in the first body. The code does this by changing the body patch properties via 'PatchHandles'. (For more information on patches in MATLAB®, see the “Introduction to Patch Objects” section in the MATLAB documentation.)

Note: On some platforms utilizing software OpenGL® rendering, the transparency may cause a decrease in animation speed.

See the `opengl` documentation for more information on OpenGL in MATLAB.

To create a transparency, the code gets the patch handles for the first body.

```
patchHandles2 = h.Bodies{1}.PatchHandles;
```

Set desired face and edge alpha values.

```
desiredFaceTransparency = .3;
desiredEdgeTransparency = 1;
```

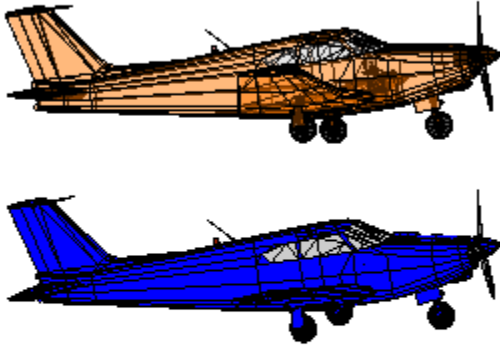
This code gets the current face and edge alpha data and changes all values to desired alpha values. In the figure, notice the first body now has a transparency.

```
for k = 1:size(patchHandles2,1)
    tempFaceAlpha = get(patchHandles2(k), 'FaceVertexAlphaData');
    tempEdgeAlpha = get(patchHandles2(k), 'EdgeAlpha');
    set(patchHandles2(k), ...
```

```

    'FaceVertexAlphaData', repmat(desiredFaceTransparency, size(tempFaceAlpha)));
set(patchHandles2(k), ...
    'EdgeAlpha', repmat(desiredEdgeTransparency, size(tempEdgeAlpha)));
end

```



Change Color of the Second Body

This code illustrates how to change the body color of the second body. The code does this by changing the body patch properties via 'PatchHandles'.

```
patchHandles3 = h.Bodies{2}.PatchHandles;
```

This code sets the desired patch color (red).

```
desiredColor = [1 0 0];
```

The code can now get the current face color data and change all values to desired color values. Note the following points on the code:

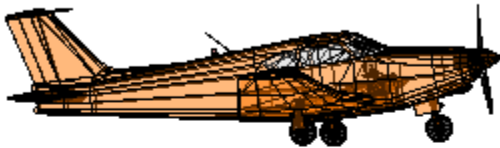
- The `if` condition keeps the windows from being colored.
- The name property is stored in the geometry data of the body (`h.Bodies{2}.Geometry.FaceVertexColorData(k).name`).
- The code only changes the indices in `patchHandles3` with non-window counterparts in the body geometry data.

The name property might not always be available to determine various parts of the vehicle. In these cases, you will need to use an alternative approach to selective coloring.

```

for k = 1:size(patchHandles3,1)
    tempFaceColor = get(patchHandles3(k), 'FaceVertexCData');
    tempName = h.Bodies{2}.Geometry.FaceVertexColorData(k).name;
    if ~contains(tempName, 'Windshield') &&...
        ~contains(tempName, 'front-windows') &&...
        ~contains(tempName, 'rear-windows')
        set(patchHandles3(k), ...
            'FaceVertexCData', repmat(desiredColor, [size(tempFaceColor,1),1]));
    end
end
end

```



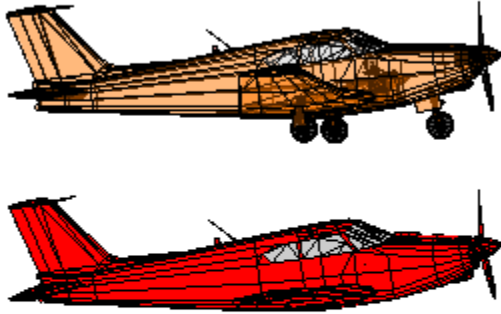
Turn Off Landing Gear on Second Body

The following code turns off the landing gear for the second body. To do this, it turns off the visibility of all vehicle parts associated with the landing gear. Note the indices into the `patchHandles3` vector were determined from the name property in the geometry data. Other data sources might not have this information available. In these cases, you will need to know which indices correspond to particular parts of the geometry.

```

for k = [1:8, 11:14, 52:57]
    set(patchHandles3(k), 'Visible', 'off')
end

```



Close and Delete Animation Object

To close and delete

```
h.delete();
```

```
 %#ok<*REPMAT>
```


Comparing Zonal Harmonic Gravity Model to Other Gravity Models

This example shows how to examine the zonal harmonic, spherical and 1984 World Geodetic System (WGS84) gravity models for latitudes from +/- 90 degrees at the surface of the Earth.

Determine Earth-Centered Earth-Fixed (ECEF) Position

Since ECEF coordinate system is geocentric, you can use spherical equations to determine the position from the latitude, longitude and geocentric radius.

Calculate the geocentric radii in meters at an array of latitudes from +/- 90 degrees using `geocradius`.

```
lat = -90:90;
r = geocradius( lat );
rlat = convang( lat, 'deg', 'rad' );
z = r.*sin(rlat);
```

Because longitude has no effect for zonal harmonic gravity model, assume that the y position is zero.

```
x = r.*cos(rlat);
y = zeros(size(x));
```

Compute Zonal Harmonic Gravity for Earth

Use `gravityzonal` to calculate array of zonal harmonic gravity in ECEF coordinates for array of ECEF positions in meters per seconds squared.

```
[gx_zonal, gy_zonal, gz_zonal] = gravityzonal([x' y' z']);
```

Calculate WGS84 Gravity

Use `gravitywgs84` to compute WGS84 gravity in down-axis and north-axis at the Earth's surface, an array of geodetic latitudes in degrees and 0 degrees longitude using the exact method with atmosphere, no centrifugal effects, and no preprocessing.

```
lat_gd = geoc2geod(lat, r);
long_gd = zeros(size(lat));
[gd_wgs84, gn_wgs84] = gravitywgs84( zeros(size(lat)), lat_gd, long_gd, 'Exact', [false true false]);
```

Determine Gravity for Spherical Earth

Compute the array of spherical gravity for the array of geocentric radii in meters per second squared using the Earth's gravitational parameter in meters cubed per second squared.

```
GM = 3.986004415e14;
gd_sphere = -GM./(r.*r);
```

Comparison Plots for Different Gravity Models

To compare the gravity models, their outputs must be in the same coordinate system. You can transform zonal gravity from ECEF coordinates to NED coordinates by using the Direction Cosine Matrix from `dcmecef2ned`.

```
dcm_ef = dcmecef2ned( lat_gd, long_gd );
gxyz_zonal = reshape([gx_zonal gy_zonal gz_zonal]', [3 1 181]);
```

```

for m = length(lat):-1:1
    gned_zonal(m,:) = (dcm_ef(:,:,m)*gxyz_zonal(:,:,m))';
end

figure(1)
plot(lat_gd, gned_zonal(:,3), lat, -gd_sphere, '--', lat_gd, gd_wgs84, '-.')
legend('Zonal Harmonic', 'Spherical', 'WGS84','Location','North')
xlabel('Geodetic Latitude (degrees)')
ylabel('Down gravity (m/s^2)')
grid

```

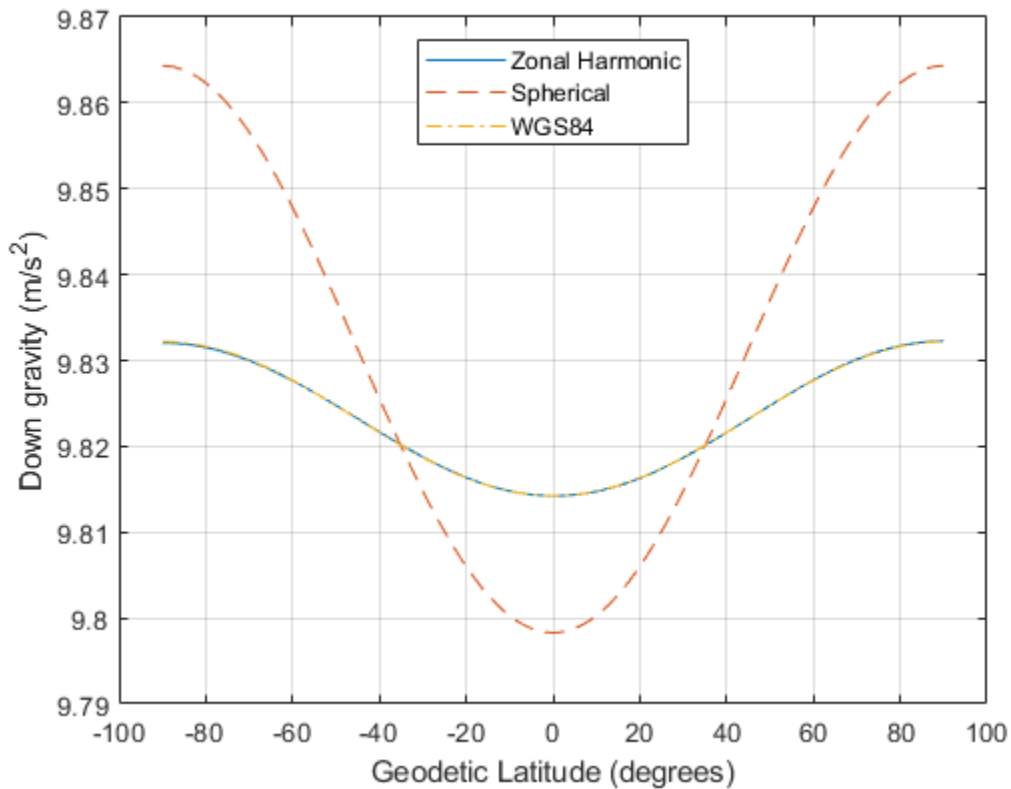


Figure 1: Gravity in the Down-axis in meters per second squared

```

figure(2)
plot( lat_gd, gned_zonal(:,1), lat_gd, gn_wgs84, 'r-.')
hold on
plot([lat(1) lat(end)], [0 0], 'g--')
legend('Zonal Harmonic', 'WGS84', 'Spherical','Location','Best')
xlabel('Geodetic Latitude (degrees)')
ylabel('North gravity (m/s^2)')
grid
hold off

```

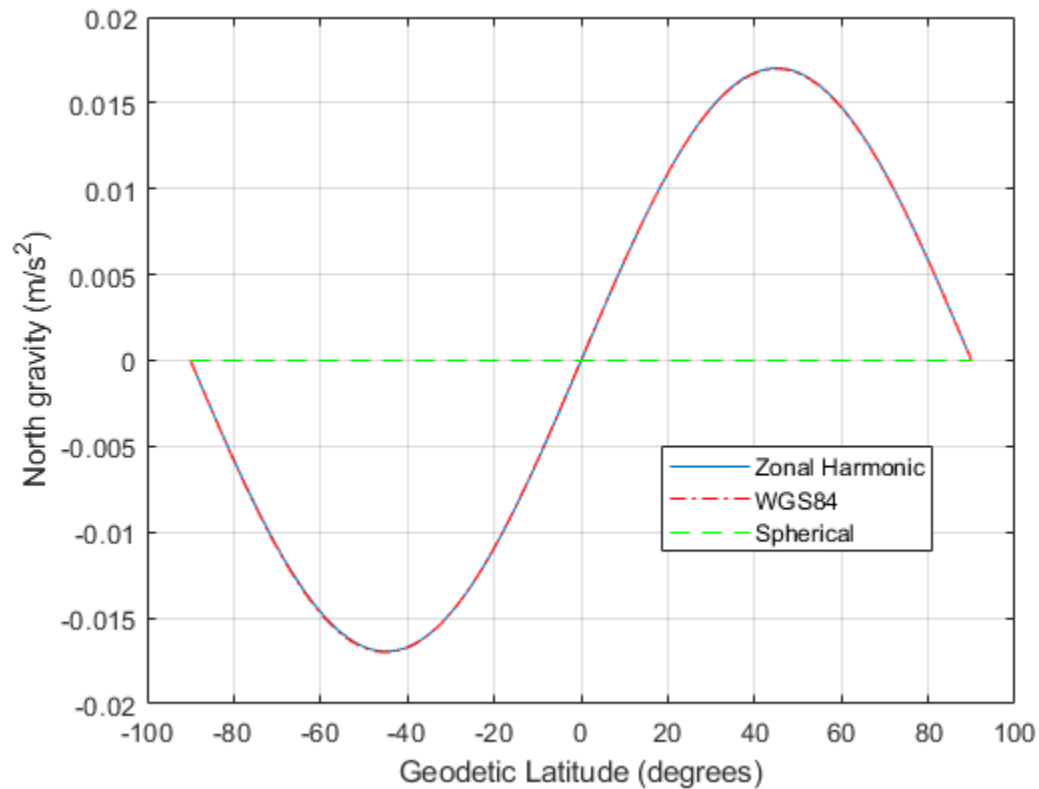


Figure 2: Gravity in the North-axis in meters per second squared

Calculate total gravity for WGS84 and from zonal gravity vector in meters per second squared.

```
gtotal_wgs84 = gravitywgs84( zeros(size(lat)), lat_gd, zeros(size(lat)), 'Exact', [false true false]);
gtotal_zonal = sqrt(sum([gx_zonal.^2 gy_zonal.^2 gz_zonal.^2],2));
```

```
figure(3)
plot( lat, gtotal_zonal, lat_gd, gtotal_wgs84, '-.' )
legend('Zonal Harmonic', 'WGS84','Location','North')
xlabel('Geodetic Latitude (degrees)')
ylabel('Total gravity (m/s^2)')
grid
```

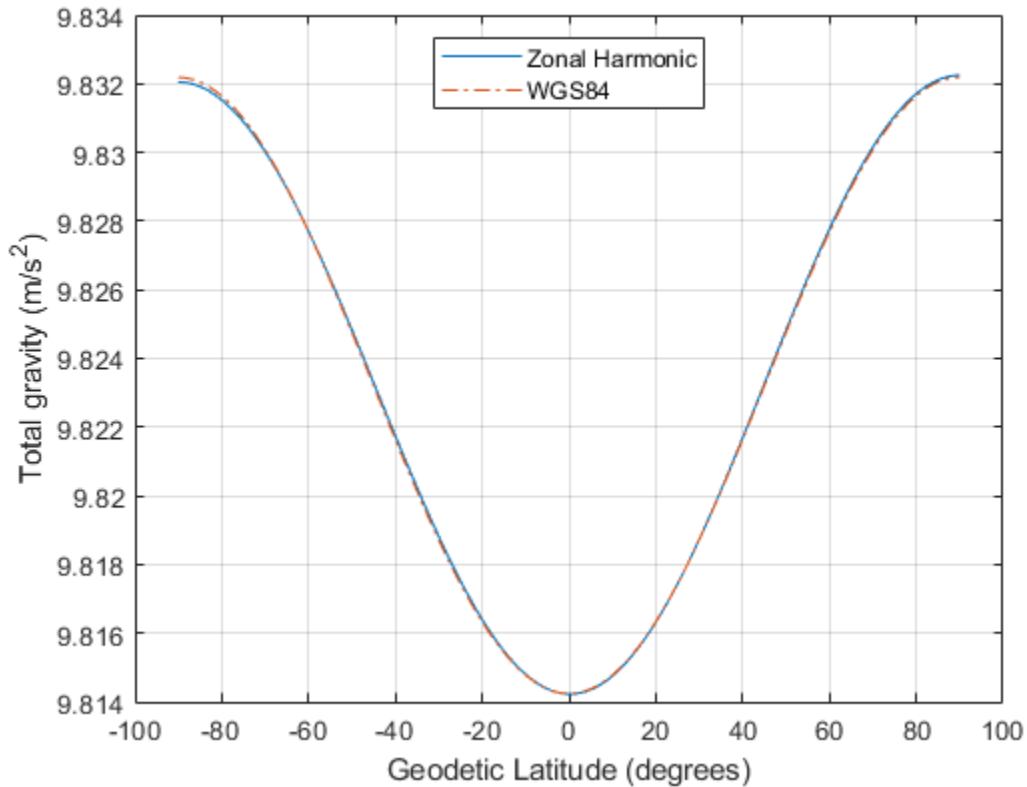


Figure 3: Total gravity in meters per second squared

Compare Gravity Models with Centrifugal Effects

Now, you have seen the gravity comparisons of a non-rotating Earth. Examine the centrifugal effects from the Earth's rotation on the gravity models.

Compute Gravity Centrifugal Effects for Earth

Use `gravitycentrifugal` to calculate array of centrifugal effects in ECEF coordinates for array of ECEF positions in meters per seconds squared.

```
[gx_cent, gy_cent, gz_cent] = gravitycentrifugal([x' y' z']);
```

Add centrifugal effects to zonal harmonic gravity.

```
gx_cent_zonal = gx_zonal + gx_cent;
gy_cent_zonal = gy_zonal + gy_cent;
gz_cent_zonal = gz_zonal + gz_cent;
```

Calculate WGS84 Gravity with Centrifugal Effects

Use `gravitywgs84` to compute WGS84 gravity in down-axis and north-axis at the Earth's surface, an array of geodetic latitudes in degrees and 0 degrees longitude using the exact method with atmosphere, centrifugal effects, and no precessing.

```
[gd_cent_wgs84, gn_cent_wgs84] = gravitywgs84( zeros(size(lat)), lat_gd, long_gd, 'Exact', [false
```

Calculate total gravity with centrifugal effects for WGS84 and from zonal gravity vector in meters per second squared.

```
gtotal_cent_wgs84 = gravitywgs84( zeros(size(lat)), lat_gd, zeros(size(lat)), 'Exact', [false fa
gtotal_cent_zonal = sqrt(sum([gx_cent_zonal.^2 gy_cent_zonal.^2 gz_cent_zonal.^2],2));
```

Comparison Plots for Different Gravity Models with Centrifugal Effects

To compare the gravity models, their outputs must be in the same coordinate system. You can transform zonal gravity from ECEF coordinates to NED coordinates by using the Direction Cosine Matrix from `dcmecef2ned`. In figure 5, you can see there is some difference between zonal harmonic gravity with centrifugal effects and WGS84 gravity with centrifugal effects. The majority of difference is due to differences between the zonal harmonic gravity and WGS84 gravity calculations.

```
gxyz_cent_zonal = reshape([gx_cent_zonal gy_cent_zonal gz_cent_zonal]', [3 1 181]);
for m = length(lat):-1:1
    gned_cent_zonal(m,:) = (dcm_ef(:,:,m)*gxyz_cent_zonal(:,:,m))';
end
```

```
figure(4)
plot(lat_gd, gned_cent_zonal(:,3), lat_gd, gd_cent_wgs84, '-.')
legend('Zonal Harmonic', 'WGS84', 'Location', 'North')
xlabel('Geodetic Latitude (degrees)')
ylabel('Down gravity (m/s^2)')
grid
```

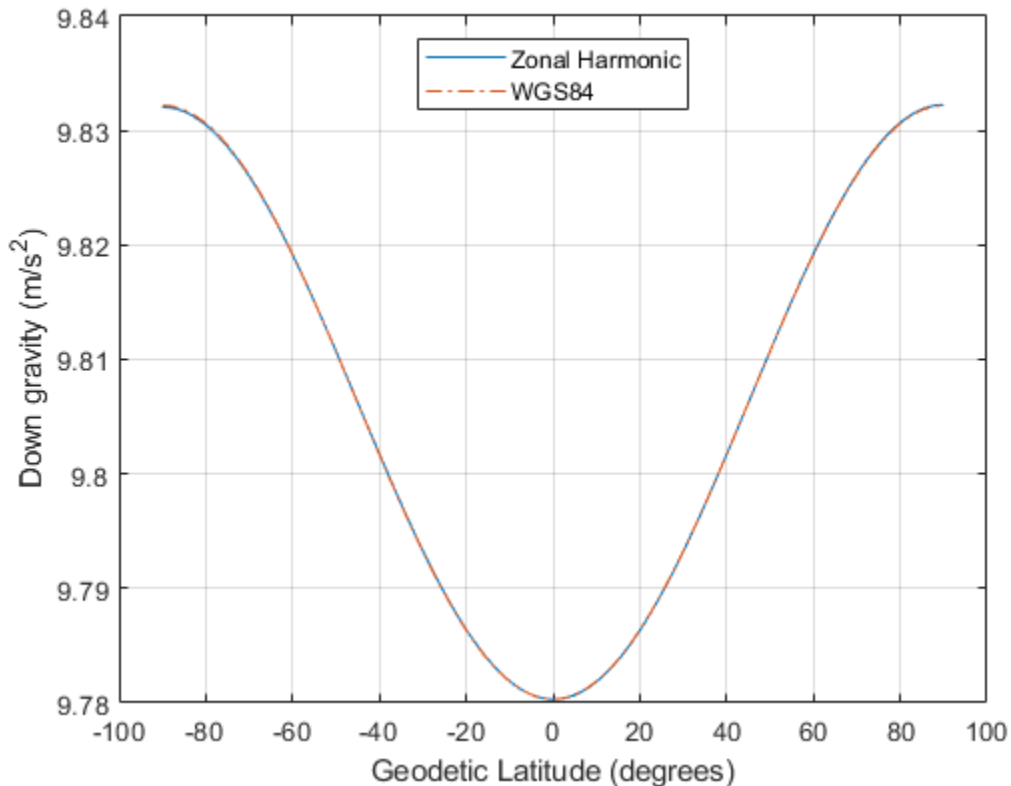


Figure 4: Gravity with centrifugal effects in the Down-axis in meters per second squared

```

figure(5)
plot( lat_gd, gned_cent_zonal(:,1), lat_gd, gn_cent_wgs84, '--', lat_gd, (gned_zonal(:,1)-gn_wgs84) )
axis([-100 100 -0.0002 0.0002])
legend('Zonal Harmonic', 'WGS84', 'Error Between Models w/o Centrifugal Effects', 'Location','North')
xlabel('Geodetic Latitude (degrees)')
ylabel('North gravity (m/s^2)')
grid

```

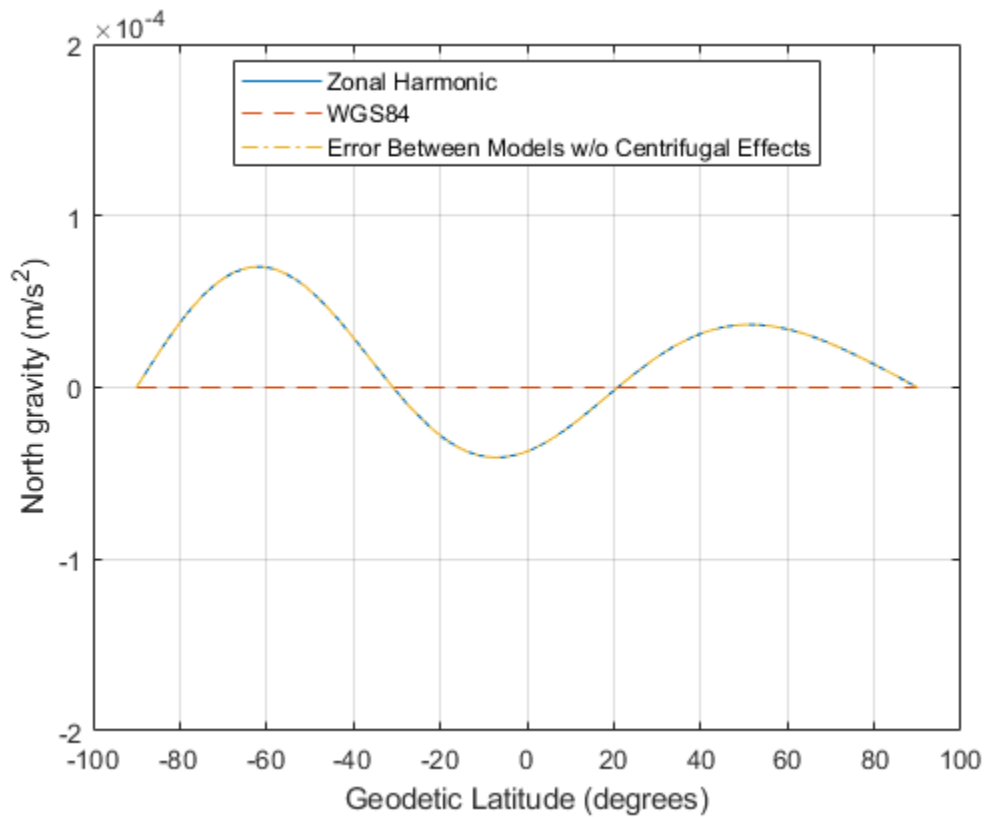


Figure 5: Gravity in the North-axis in meters per second squared

```

figure(6)
plot( lat, gtotal_cent_zonal, lat_gd, gtotal_cent_wgs84, '-.' )
legend('Zonal Harmonic', 'WGS84', 'Location', 'North')
xlabel('Geodetic Latitude (degrees)')
ylabel('Total gravity (m/s^2)')
grid

```

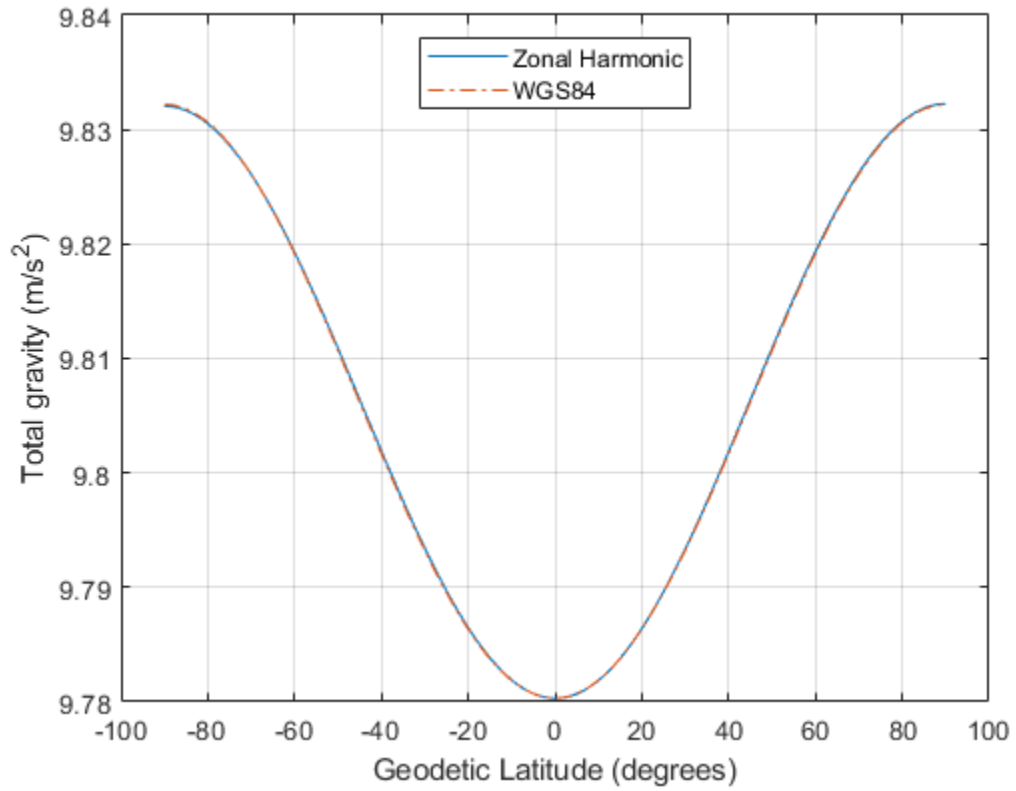


Figure 6: Total gravity with centrifugal effects in meters per second squared

Visualize Aircraft Takeoff via Virtual Reality Animation Object

This example shows how to visualize aircraft takeoff and chase helicopter with the virtual reality animation object. In this example, you can use the `Aero.VirtualRealityAnimation` object to set up a virtual reality animation based on the `asttkoff.wrl` file. The scene simulates an aircraft takeoff. The example adds a chase vehicle to the simulation and a chase viewpoint associated with the new vehicle.

Create the Animation Object

This code creates an instance of the `Aero.VirtualRealityAnimation` object.

```
h = Aero.VirtualRealityAnimation;
```

Set the Animation Object Properties

This code sets the number of frames per second and the seconds of animation data per second time scaling. 'FramesPerSecond' controls the rate at which frames are displayed in the figure window. 'TimeScaling' is the seconds of animation data per second time scaling.

The 'TimeScaling' and 'FramesPerSecond' properties determine the time step of the simulation. The settings in this example result in a time step of approximately 0.5s. The equation is:

$(1/\text{FramesPerSecond}) * \text{TimeScaling}$ + extra terms to handle for sub-second precision.

```
h.FramesPerSecond = 10;  
h.TimeScaling = 5;
```

This code sets the `.wrl` file to be used in the virtual reality animation.

```
h.VRWorldFilename = [matlabroot, '/toolbox/aero/astdemos/asttkoff.wrl'];
```

Change Directory

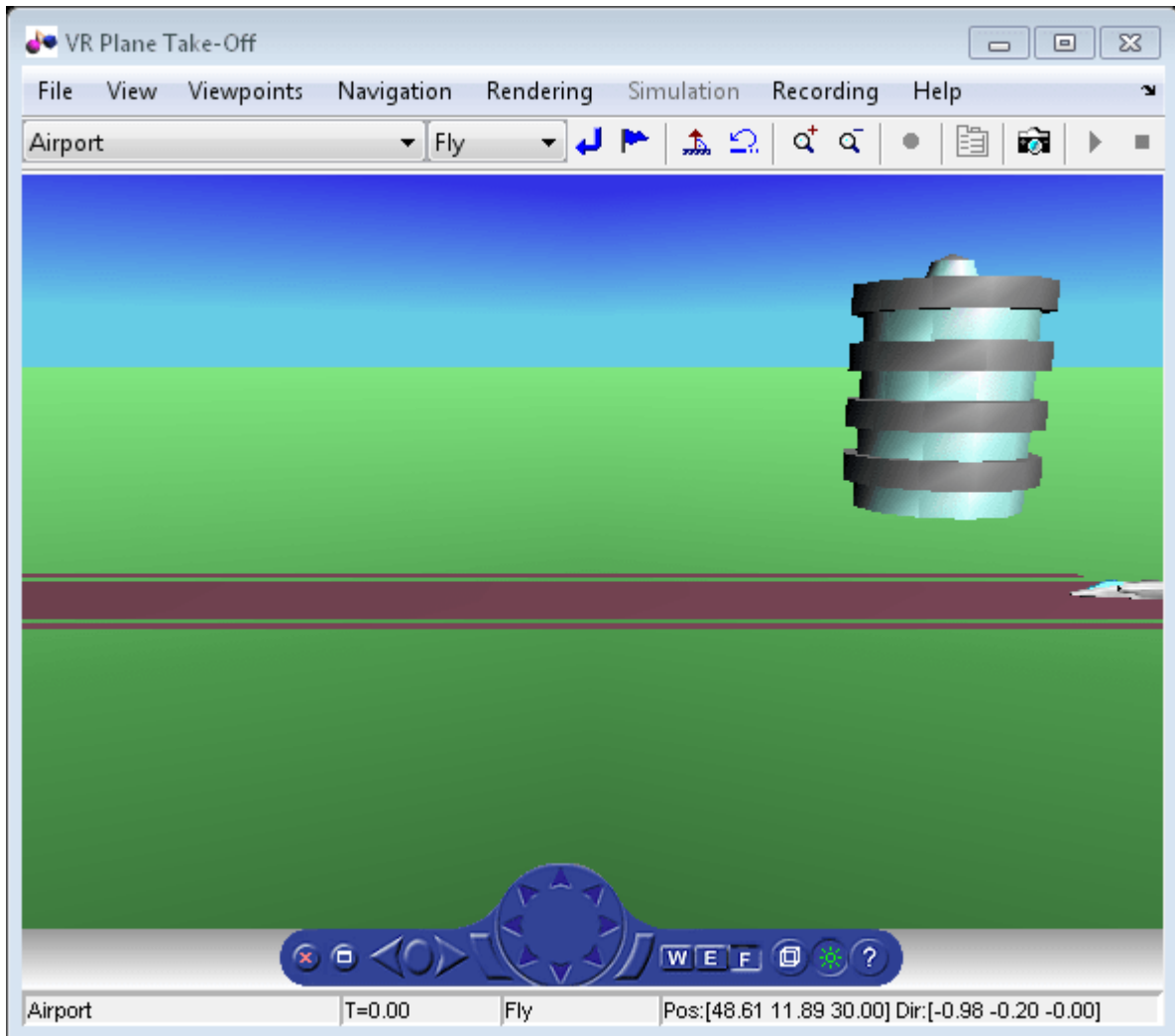
The `VirtualRealityAnimation` object methods use temporary `.wrl` files to keep track of changes to the world. This requires the directory containing the original `.wrl` file to be writable. This code runs the example from a temporary directory to ensure there are no issues with directory permissions. Note, a license for Simulink® 3D Animation™ is required to run this example.

```
% Copy file to temporary directory  
copyfile(h.VRWorldFilename, [tempdir, 'asttkoff.wrl'], 'f');  
% Set world filename to the copied .wrl file.  
h.VRWorldFilename = [tempdir, 'asttkoff.wrl'];
```

Initialize the Virtual Reality Animation Object

The `initialize` method loads the animation world described in the 'VRWorldFilename' field of the animation object. When parsing the world, node objects are created for existing nodes with DEF names. The `initialize` method also opens the Simulink 3D Animation viewer.

```
h.initialize();
```

Set Additional Node Information

This code sets simulation timeseries data. `takeoffData.mat` contains logged simulated data. `takeoffData` is set up as a 'StructureWithTime', which is one of the default data formats.

```
load takeoffData
[~, idxPlane] = find(strcmp('Plane', h.nodeInfo));
h.Nodes{idxPlane}.TimeseriesSource = takeoffData;
h.Nodes{idxPlane}.TimeseriesSourceType = 'StructureWithTime';
```

Set Coordinate Transform Function

The virtual reality animation object expects positions and rotations in aerospace body coordinates. If the input data is different, you must create a coordinate transformation function in order to correctly line up the position and rotation data with the surrounding objects in the virtual world. This code sets the coordinate transformation function for the virtual reality animation.

In this particular case, if the input translation coordinates are $[x1, y1, z1]$, they must be adjusted as follows: $[X, Y, Z] = -[y1, x1, z1]$. The custom transform function can be seen here: `matlabroot/toolbox/aero/astdemos/vranimCustomTransform.m`

```
h.Nodes{idxPlane}.CoordTransformFcn = @vranimCustomTransform;
```

Add a Chase Helicopter

This code shows how to add a chase helicopter to the animation object.

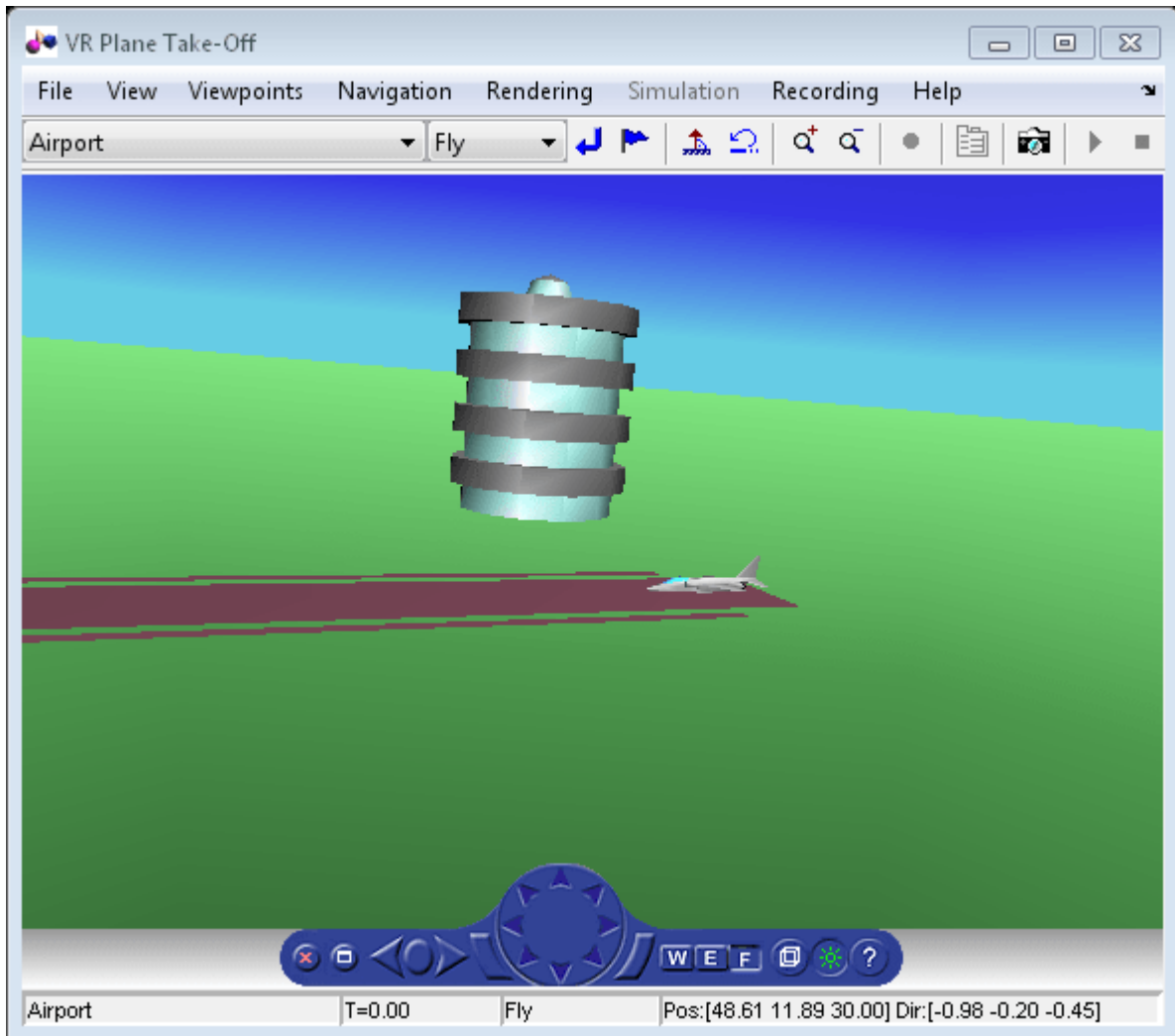
You can view all the nodes currently in the virtual reality animation object by using the `nodeInfo` method. When called with no output argument, this method prints the node information to the command window. With an output argument, the method sets node information to that argument.

```
h.nodeInfo;
```

```
Node Information
1   Camera1
2   Plane
3   _v2
4   Block
5   Terminal
6   _v3
7   Lighthouse
8   _v1
```

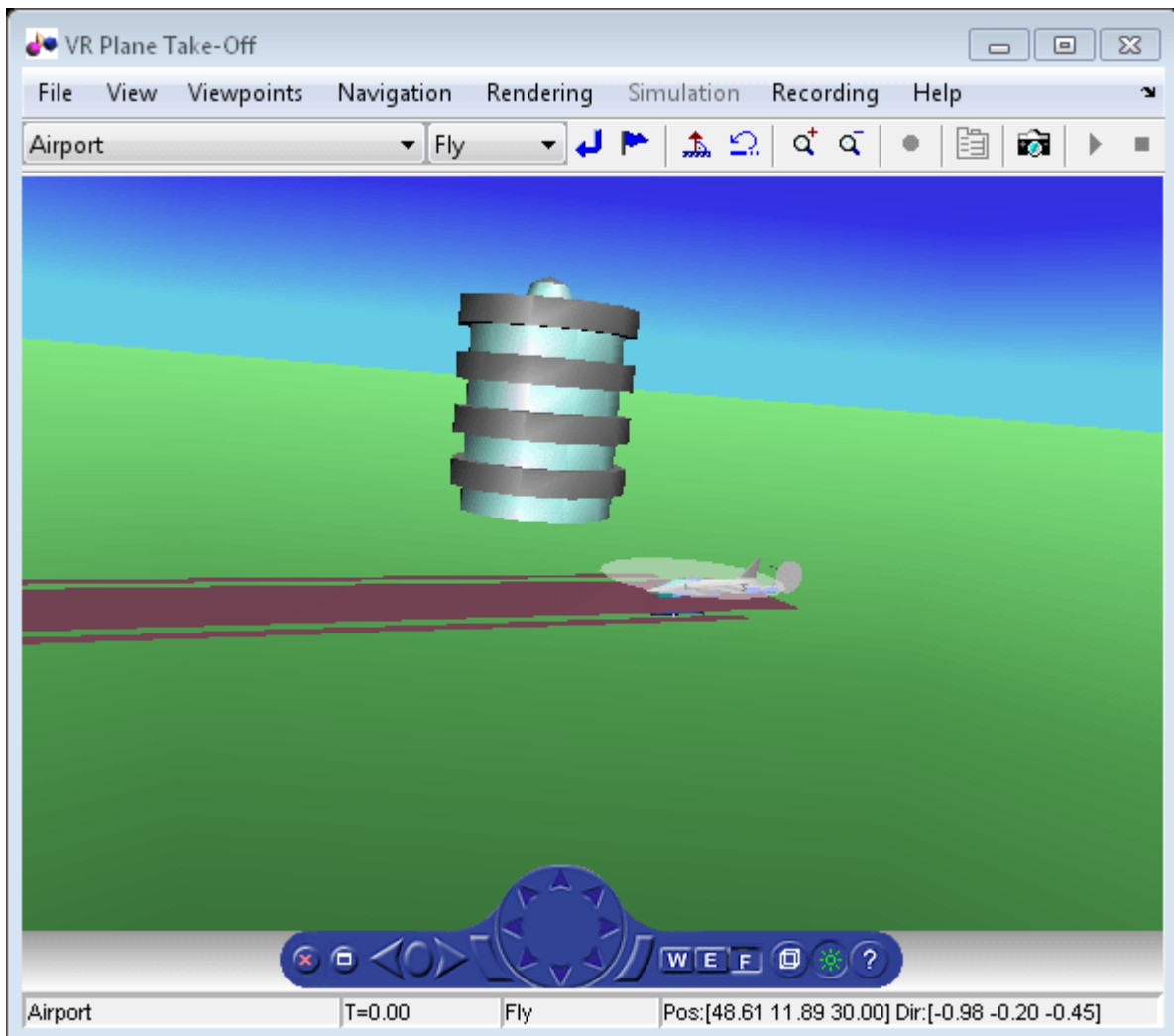
This code moves the camera angle of the virtual reality figure to view the aircraft.

```
set(h.VRFigure, 'CameraDirection',[0.45 0 -1]);
```



Use the `addNode` method to add another node to the object. By default, each time you add or remove a node or route, or when you call the `saveas` method, Aerospace Toolbox displays a message about the current `.wrl` file location. To disable this message, set the `ShowSaveWarning` property in the `VirtualRealityAnimation` object.

```
h.ShowSaveWarning = 0;
h.addNode('Lynx',[matlabroot,'/toolbox/aero/astdemos/chaseHelicopter.wrl']);
```



Another call to `nodeInfo` shows the newly added Node objects.

`h.nodeInfo`

```
Node Information
1   Camera1
2   Plane
3   _V2
4   Block
5   Terminal
6   _v3
7   Lighthouse
8   _v1
9   Lynx
10  Lynx_Inline
```

Adjust newly added helicopter to sit on runway.

```
[~, idxLynx] = find(strcmp('Lynx',h.nodeInfo));
h.Nodes{idxLynx}.VRNode.translation = [0 1.5 0];
```

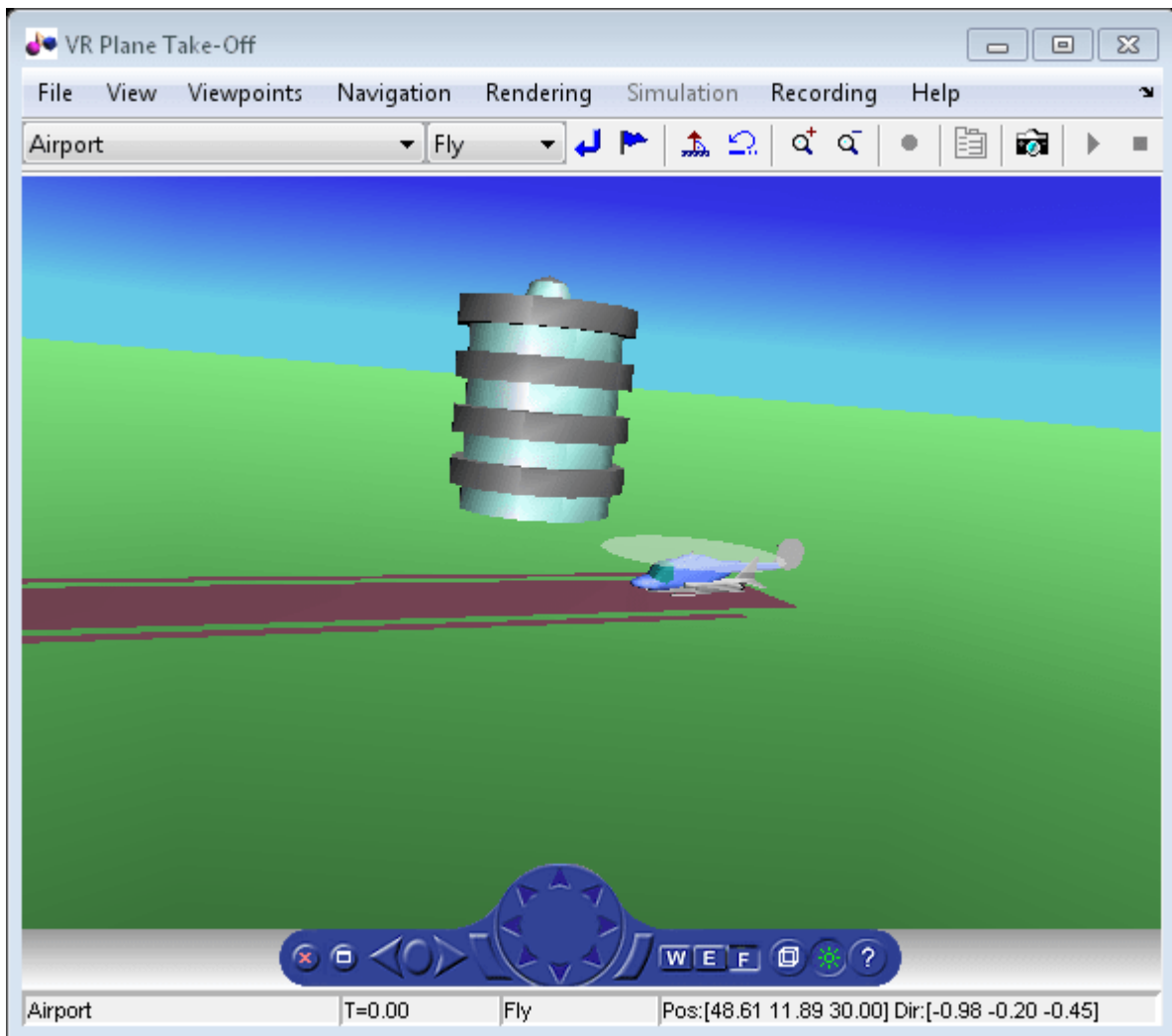
This code sets data properties for the chase helicopter. The 'TimeseriesSourceType' is the default 'Array6DoF', so no additional property changes are needed. The same coordinate transform function (vranimCustomTransform) is used for this node as the preceding node. The previous call to nodeInfo returned the node index (2).

```
load chaseData
h.Nodes{idxLynx}.TimeseriesSource = chaseData;
h.Nodes{idxLynx}.CoordTransformFcn = @vranimCustomTransform;
```

Create New Viewpoint

This code uses the addViewpoint method to create a new viewpoint named 'chaseView'. The new viewpoint will appear in the viewpoint pull-down menu in the virtual reality window as "View From Helicopter". Another call to nodeInfo shows the newly added node objects. The node is created as a child of the chase helicopter.

```
h.addViewpoint(h.Nodes{idxLynx}.VRNode, 'children', 'chaseView', 'View From Helicopter');
```



Play Animation

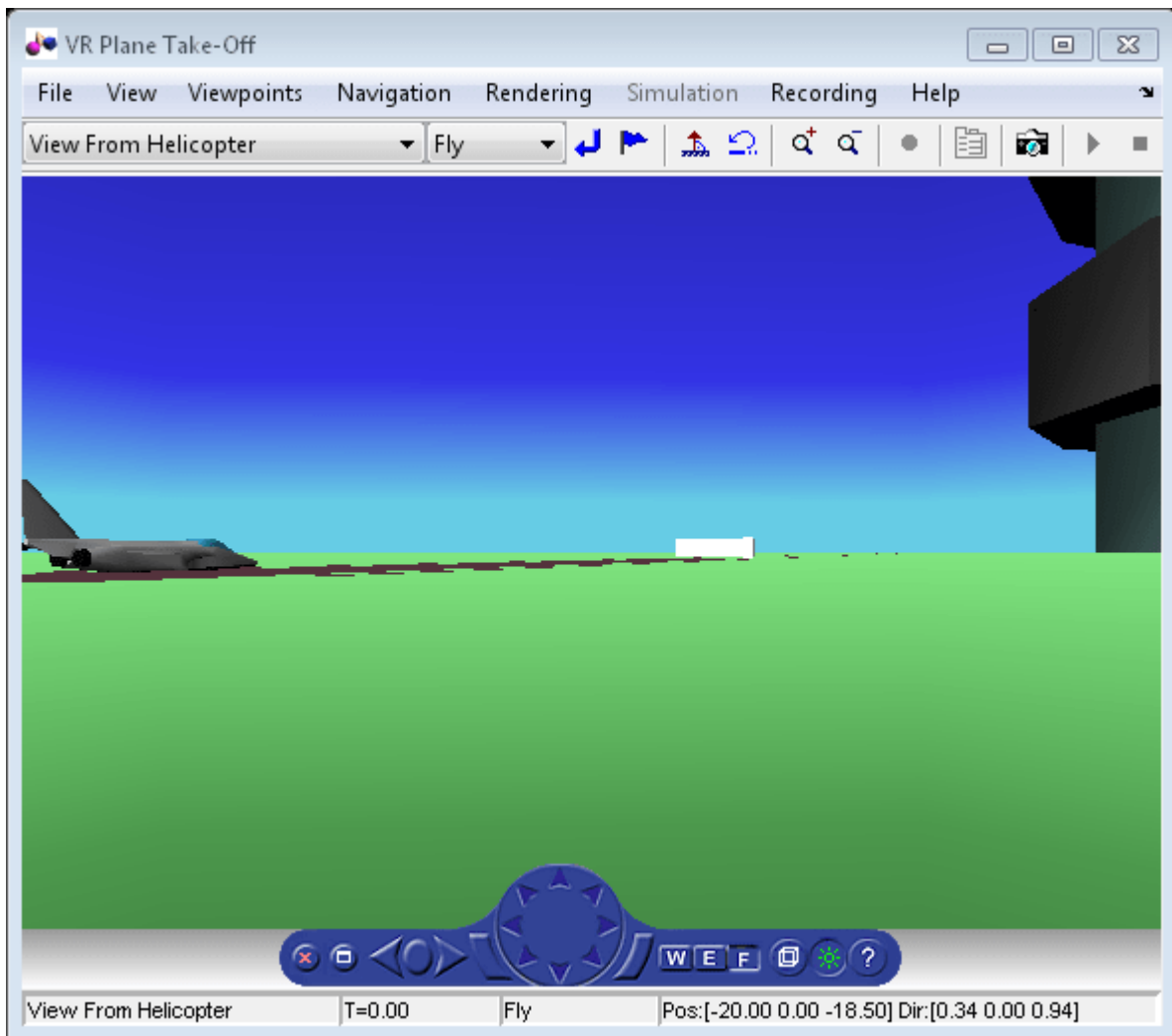
The play method runs the simulation for the specified timeseries data.

```
h.play();
```

Play Animation From Helicopter

This code sets the orientation of the viewpoint via the `vrnode` object associated with the node object for the viewpoint. In this case, it will change the viewpoint to look out the left side of the helicopter at the plane.

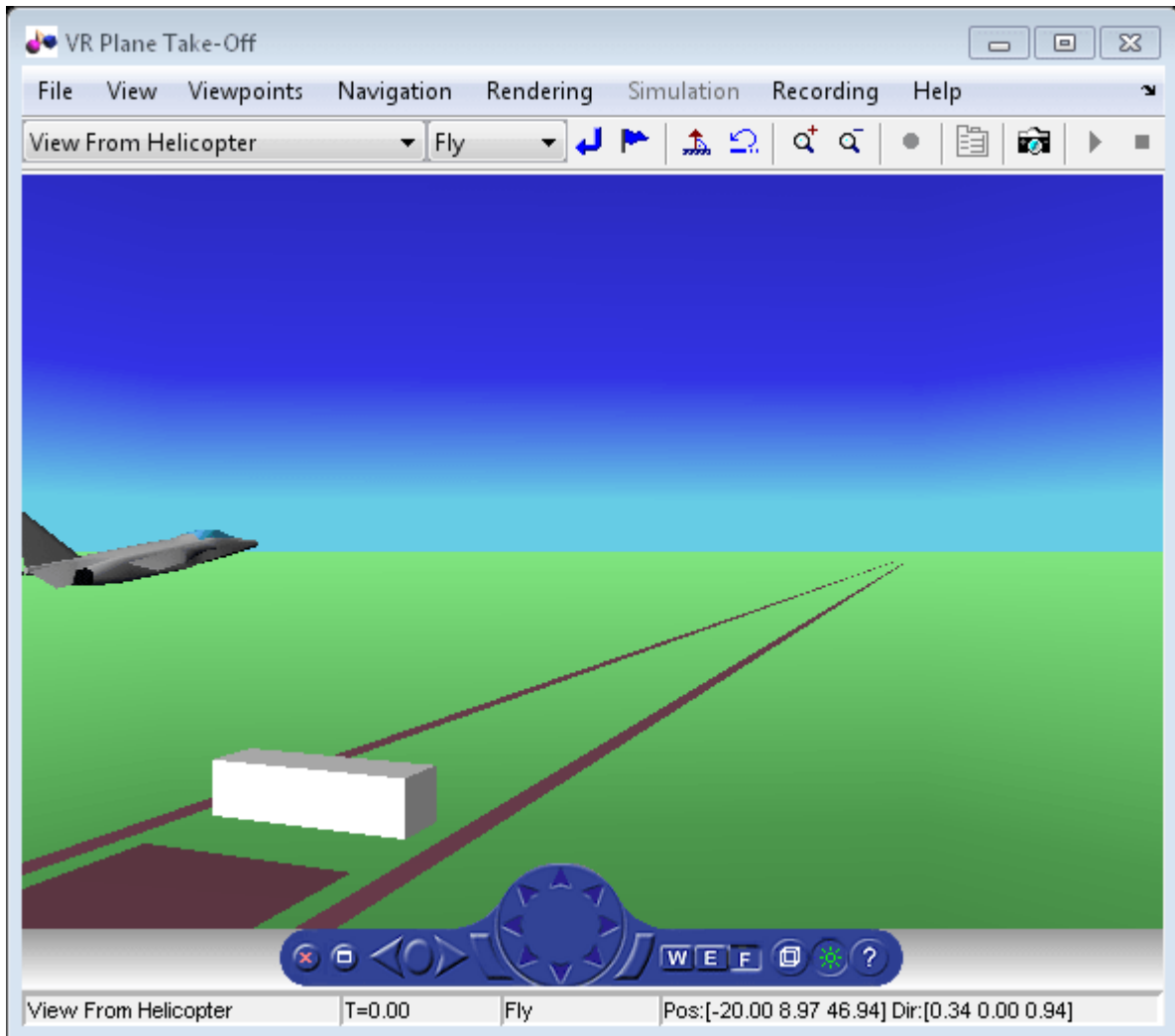
```
[~, idxChaseView] = find(strcmp('chaseView',h.nodeInfo));
h.Nodes{idxChaseView}.VRNode.orientation = [0 1 0 convang(200,'deg','rad')];
set(h.VRFigure,'Viewpoint','View From Helicopter');
```



Add ROUTE

This code calls the `addRoute` method to add a ROUTE command to connect the plane position to the Camera1 node. This will allow for the "Ride on the Plane" viewpoint to function as intended.

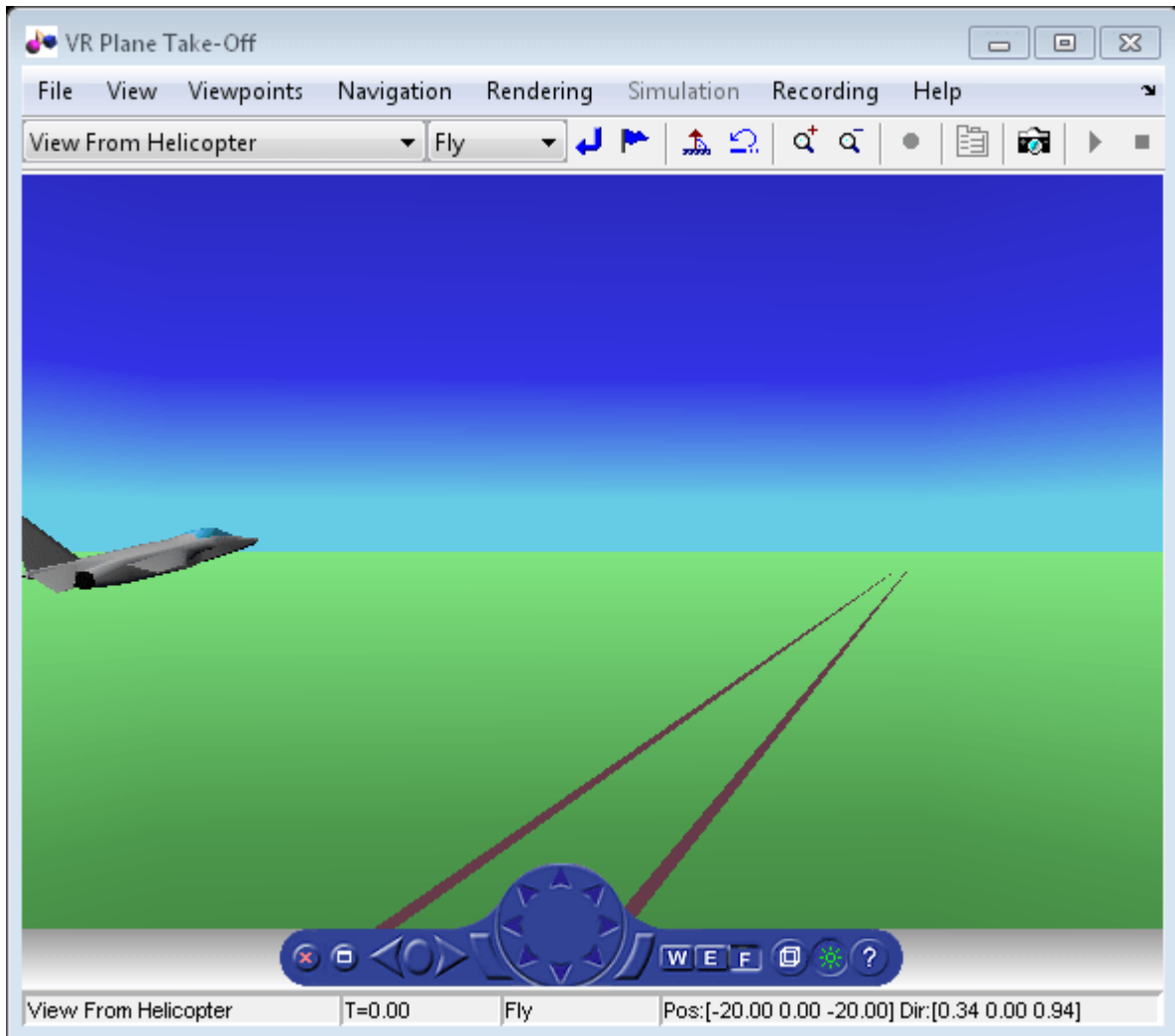
```
h.addRoute('Plane','translation','Camera1','translation');
```



The scene from the helicopter viewpoint

This code plays the animation.

```
h.play();
```



Add Another Body

This code adds another helicopter to the scene. It also changes to another viewpoint to view all three bodies in the scene at once.

```
set(h.VRFigure, 'Viewpoint', 'See Whole Trajectory');
h.addNode('Lynx1', [matlabroot, '/toolbox/aero/astdemos/chaseHelicopter.wrl']);
h.nodeInfo
```

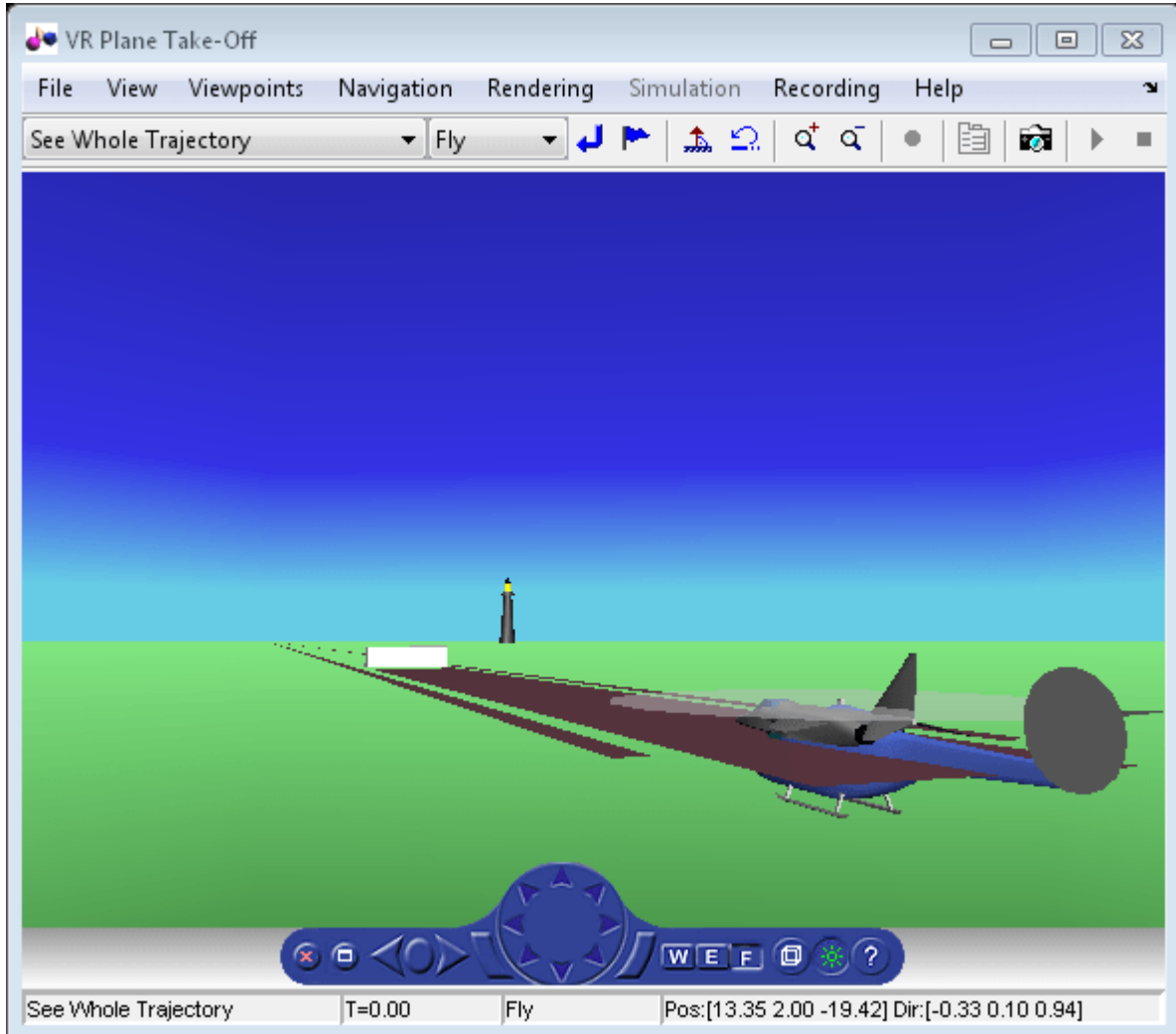
```
Node Information
1   Camera1
2   Plane
3   _v2
4   Block
5   Terminal
6   _v3
7   Lighthouse
8   _v1
9   Lynx
10  Lynx_Inline
```



```

11 chaseView
12 Lynx1
13 Lynx1_Inline

```



Adjust newly added helicopter to sit above runway.

```

[~, idxLynx1] = find(strcmp('Lynx1',h.nodeInfo));
h.Nodes{idxLynx1}.VRNode.translation = [0 1.3 0];

```

Remove Body

This code uses the `removeNode` method to remove the second helicopter. `removeNode` takes either the node name or node index (as obtained from `nodeInfo`). The associated inline node is removed as well.

```

h.removeNode('Lynx1');
h.nodeInfo

```

```

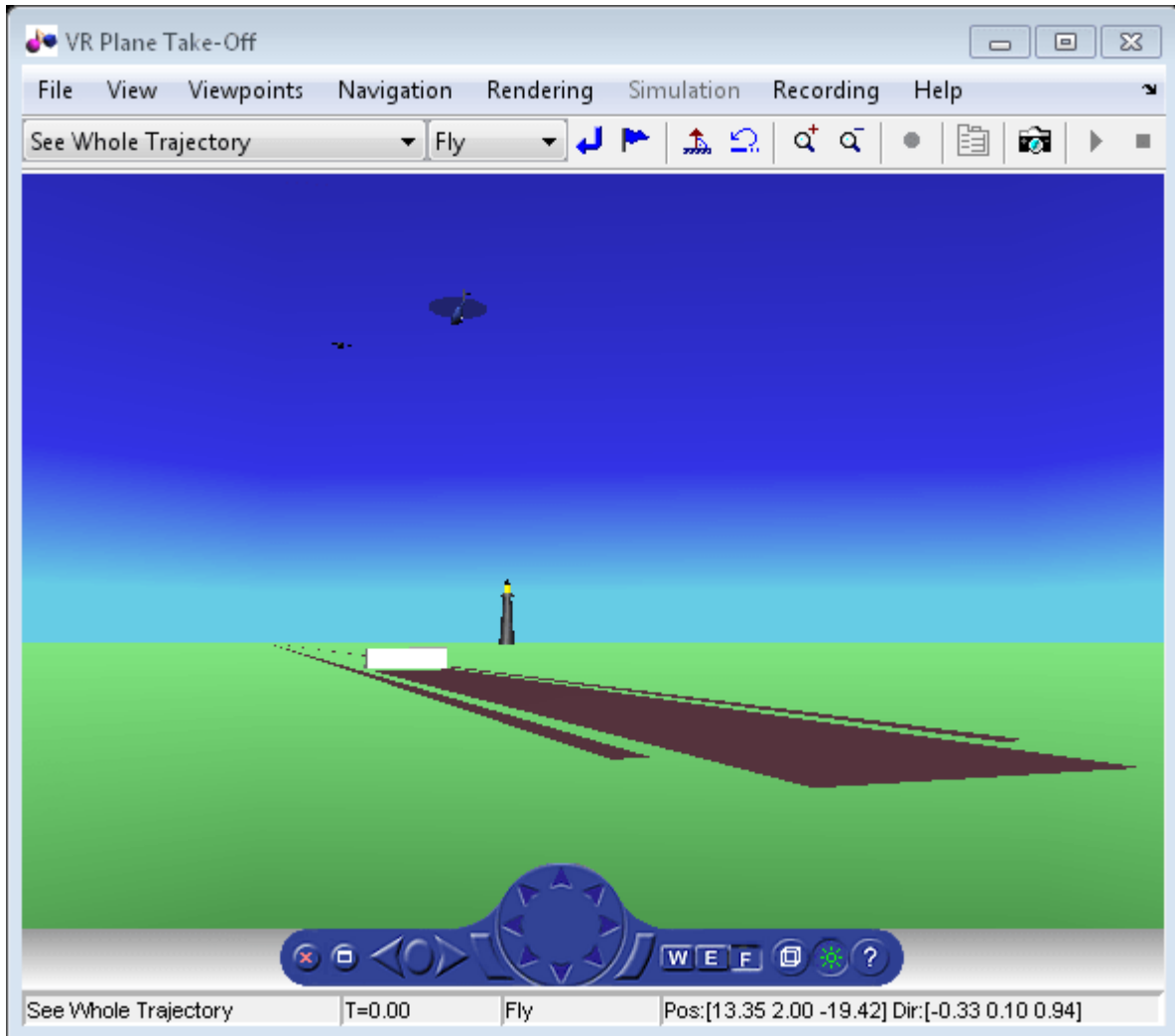
Node Information
1 Camera1

```

```

2   Plane
3   _V2
4   Block
5   Terminal
6   _v3
7   Lighthouse
8   _v1
9   Lynx
10  Lynx_Inline
11  chaseView

```



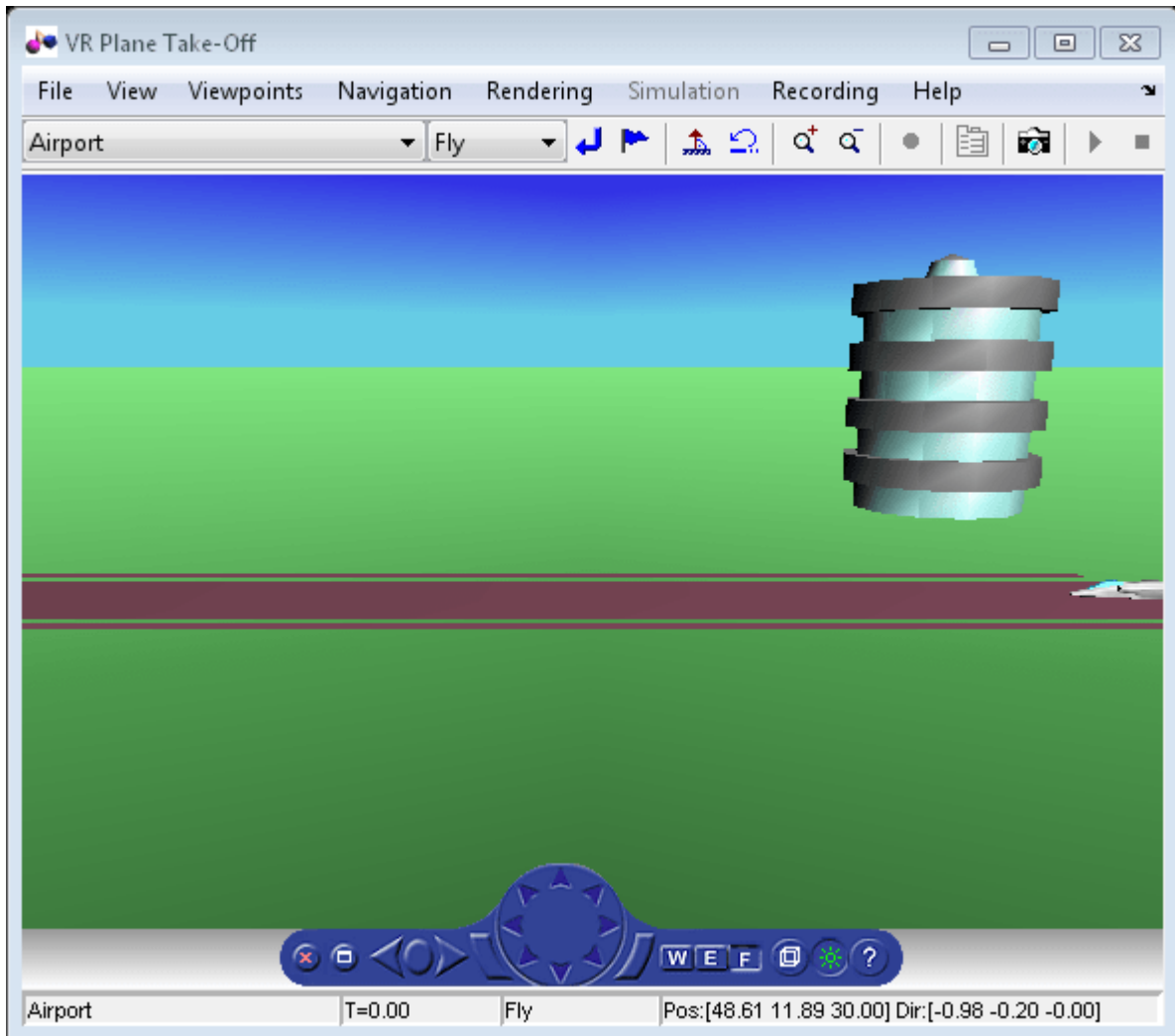
Revert To Original World

The original filename is stored in the 'VRWorldOldFilename' property of the animation object. To bring up the original world, set 'VRWorldFilename' to the original name and reinitializing it.

```

h.VRWorldFilename = h.VRWorldOldFilename{1};
h.initialize();

```



Close and Delete World

To close and delete

```
h.delete();
```

Calculating Compressor Power Required in a Supersonic Wind Tunnel

This example shows how to calculate the required compressor power in a supersonic wind tunnel.

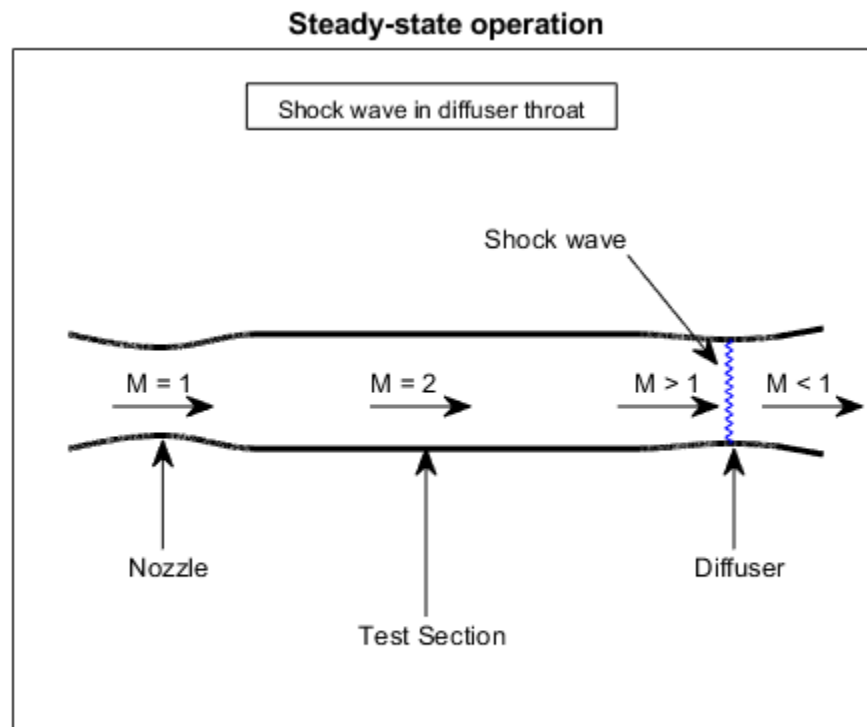
Problem Definition

This section describes the problem to be solved. It also provides necessary equations and known values.

Calculate how much compressor power is required to run a fixed geometry supersonic wind tunnel at steady-state and startup to simulate operating conditions of Mach 2 flow at an altitude of 20 kilometers.

The test section is circular with a diameter of 25 centimeters. After the test section is a fixed-area diffuser. The wind tunnel uses a cooler to reject extra energy that is added to the system by the compressor. Therefore, the compressor inlet and the test section have the same stagnation temperature. Assume the compressor is isentropic and friction effects are negligible.

```
steadyPicture = astsswtschematic('steady');
```



The given information in the problem is:

```
diameter = 25/100; % Diameter of the cross-section [m]
height = 20e+03; % Design altitude [m]
testMach = 2.0; % Mach number in the test section [dimensionless]
```

The fluid is assumed to be air and therefore it has the following properties.

```
k = 1.4;           % Specific heat ratio [dimensionless]
cp = 1.004;       % Specific heat at constant pressure [kJ / (kg * K)]
```

The cross-section area of the test section is needed from the diameter.

```
testSectionArea = pi * (diameter)^2 / 4 ; % [m^2]
```

Because the design altitude is given, solve for the flight conditions at that altitude. The Aerospace Toolbox has several functions to calculate the conditions at various altitudes. One such function, `atmosisa`, uses the International Standard Atmosphere to calculate the flight conditions on the left hand side given an altitude input:

```
[testSectionTemp, testSectionSpeedOfSound, testSectionPressure, testSectionDensity] = atmosisa(h)
```

This function uses the following units:

```
testSectionTemp = Static temperature in the test section      [K]
testSectionSpeedOfSound = Speed of sound in the test section [m / s]
testSectionPressure = Static pressure in the test section     [kPa]
testSectionDensity = Density of the fluid in the test section [kg / m^3]
```

Calculation of the Stagnation Quantities

You must calculate many of the stagnation (total) quantities in the test section. The ratios of local static conditions to the stagnation conditions can be calculated with `flowisentropic`.

```
[~,tempRatioIsen, presRatioIsen, ~, areaRatioIsen] = flowisentropic(k, testMach);
```

All of the left hand side quantities are dimensionless ratios. Now we can use the ratio of static temperature to stagnation temperature to calculate the stagnation temperature.

```
testSectionStagTemp = testSectionTemp / tempRatioIsen;
```

The optimum condition for steady-state operation of a supersonic wind tunnel with a fixed-area diffuser occurs when a normal shock is present at the diffuser throat. For optimum condition, the area of the diffuser throat must be smaller than the area of the nozzle throat. Assuming a perfect gas with constant specific heats, calculate the factor by which the diffuser area must be smaller than the nozzle area. This calculation is from a simplified form of the conservation of mass equation involving total pressures and cross-sectional areas:

$$p_{t_{nozzle}} A_{nozzle}^* = p_{t_{diffuser}} A_{diffuser}^*$$

where

$$p_{t_{nozzle}} = \text{Total pressure at the nozzle}$$

$$p_{t_{diffuser}} = \text{Total pressure at the diffuser}$$

$$A_{nozzle}^* = \text{Reference area for sonic flow at the nozzle}$$

$$A_{diffuser}^* = \text{Reference area for sonic flow at the diffuser}$$

Rearrange the equation:

$$\frac{A_{diffuser}^*}{A_{nozzle}^*} = \frac{P_{t_{nozzle}}}{P_{t_{diffuser}}}$$

This example assumes the nozzle throat area, the test section, and the region of flow at the diffuser throat before the shock to be upstream. Because the shock wave is at the throat of the diffuser, the diffuser throat area can be considered either upstream or downstream of the shock. This example assumes the diffuser throat area to be downstream. Since the upstream flow is isentropic until the shock wave, you can use the test section Mach number as the upstream Mach number. Doing this enables you to calculate the total pressure ratio through the shock and then the area ratio between the nozzle and the diffuser area.

The total pressure ratio is:

$$stagPressRatio = \frac{P_{t_{diffuser}}}{P_{t_{nozzle}}}$$

Calculate the total pressure ratio using the normal shock function from the Aerospace Toolbox:

```
[~, ~, ~, ~, ~, stagPressRatio] = flownormalshock(k, testMach);
```

The area ratio at the shock is:

$$areaRatioShock = \frac{A_{nozzle}^*}{A_{diffuser}^*}$$

We have the following expression using the conservation of mass as discussed previously.

```
areaRatioShock = stagPressRatio;
```

Calculate the area of the diffuser:

```
diffuserArea = testSectionArea / (areaRatioShock * areaRatioIsen);
```

Because the diffuser throat area is smaller than the test section area, the Mach number of the flow must converge toward unity. Using `flowisentropic` with the area ratio as the input, calculate the Mach number just upstream of the shock:

```
diffuserMachUpstreamOfShock = flowisentropic(k, (1 / areaRatioShock), 'sup');
```

Use `flownormalshock` to calculate the flow properties through the shock wave. Note, here again, we will only need the total pressure ratio:

```
[~, ~, ~, ~, ~, P0] = flownormalshock(k, diffuserMachUpstreamOfShock);
```

Calculation of Work and Power Required for the Steady-State Case

The work done by the compressor per unit mass of fluid equals the enthalpy change through the compressor. From the definition of enthalpy, calculate the specific work done by knowing the temperature change and the specific heat of the fluid at constant pressure:

$$specificWork = h_{out} - h_{in} = c_p(T_{out} - T_{in})$$

For an isentropic compressor,

$$\frac{T_{out}}{T_{in}} = \left(\frac{p_{out}}{p_{in}} \right)^{\frac{k-1}{k}}$$

Rearrange the above equation to solve for the temperature difference. Recall that the temperature into the compressor is the same as the test section stagnation temperature.

$$T_{out} - T_{in} = T_{in} \left[\left(\frac{p_{out}}{p_{in}} \right)^{\frac{k-1}{k}} - 1 \right]$$

```
tempDiff = testSectionStagTemp * ((1 / P0)^((k - 1) / k) - 1); % [K]
```

Now the specific work can be found.

```
specificWork = cp * tempDiff; % [kJ / kg]
```

The power required equals the specific work times the mass flow rate. During steady-state operation, the mass flow rate through the test section is given by:

$$\dot{m} = \rho AV = \rho A M a$$

where all flow quantities are the values in the test section:

\dot{m} = Mass flow rate

ρ = Density

A = Cross-sectional area of test section

V = Velocity

M = Mach number

a = Local speed of sound

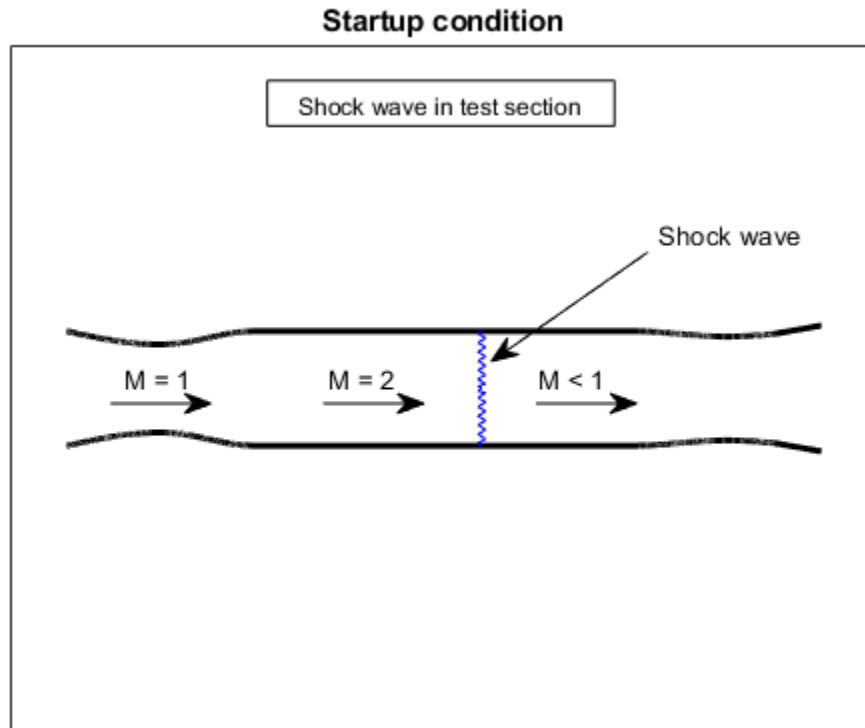
```
massFlowRate = testSectionDensity * testSectionArea * testMach * testSectionSpeedOfSound; % [kg / s]
```

Finally, calculate the power required by the compressor during steady-state operation.

```
powerSteadyState = specificWork * massFlowRate; % [kW]
```

Calculating Work and Power Required During Startup

```
startupPicture = astsswtschematic('startup');
```



For the startup condition the shock wave is in the test section. The Mach number immediately before the shock wave is the test section Mach number.

```
[~, ~, ~, ~, ~, stagPressRatioStartup] = flownormalshock(k, testMach);
```

Now, calculate the specific work of the isentropic compressor.

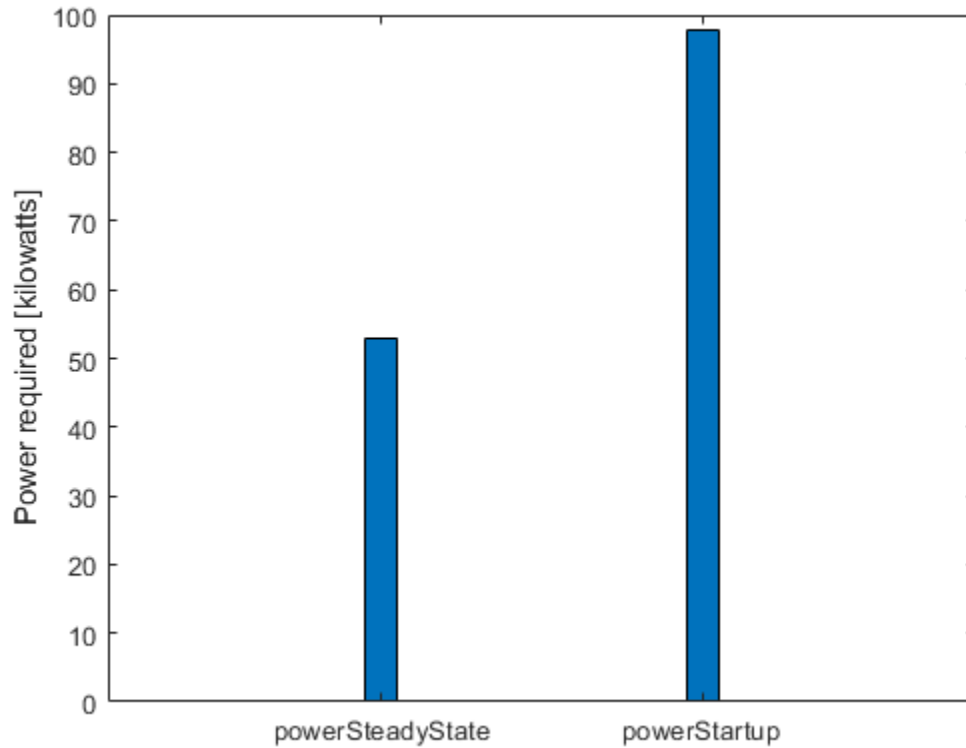
```
specificWorkStartup = cp * testSectionStagTemp * ((1 / stagPressRatioStartup)^((k - 1) / k) - 1)
```

Then, calculate the power required during startup:

```
powerStartup = specificWorkStartup * massFlowRate;    % [kW]
```

The power required during steady-state operation (53.1 kW) is much lower than that required by the compressor during startup (97.9 kW) These power required results represent the optimum and worst-case operation conditions, respectively.

```
power = [powerSteadyState powerStartup];
barGraph = figure('name', 'barGraph');
bar(power, 0.1);
ylabel('Power required [kilowatts]')
set(gca, 'XTickLabel', {'powerSteadyState', 'powerStartup'})
```

```
close(steadyPicture, startupPicture, barGraph)
```

Reference

[1] James, J. E. A., "Gas Dynamics, Second Edition", Allyn and Bacon, Inc, Boston, 1984.

Analyzing Flow with Friction Through an Insulated Constant Area Duct

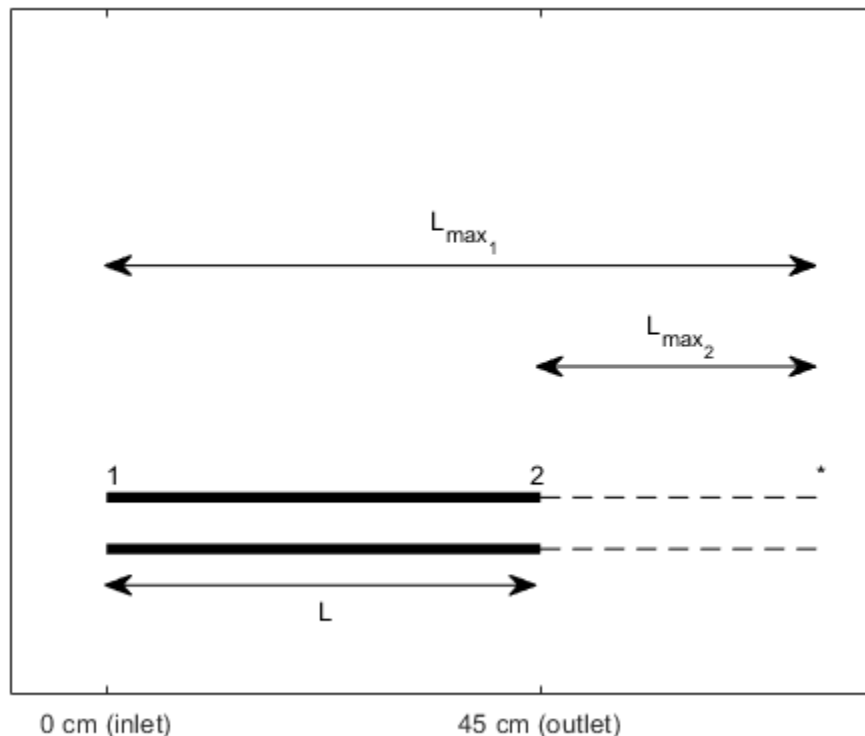
This example shows how to implement a steady, viscous flow through an insulated, constant-area duct using the Aerospace Toolbox™ software. This flow is also called Fanno line flow.

Problem Definition

This section describes the problem to be solved. It also provides necessary equations and known values.

Fanno line flow is the modeling of perfect gas flow through a constant-area duct that does not change with time and which is adiabatic. Wall friction is the main mechanism for the change of the flow variables. This example looks at Fanno flow of air entering a 3 centimeter diameter pipe that is 45 centimeters long at a Mach number of 0.6. The conditions at the inlet, also called station 1, are static pressure of 150 kilopascals and static temperature of 300 Kelvin. The duct is assumed to have a coefficient of friction of 0.02. Calculate the Mach number, static pressure and static temperature at the exit of the duct or station 2.

```
ductPicture = astfrictionduct;
```



The given information in the problem is:

```
ductLength      = 0.45;    % Length of the duct [m]
diameter        = 0.03;    % Diameter of the duct [m]
```

```

inletMach      = 0.6;      % Mach number at the duct inlet [dimensionless]
inletPressure  = 150;     % Static pressure at the duct inlet [kPa]
inletTemperature = 300;   % Static temperature at the duct input [K]
frictionCoeff  = 0.02;    % Duct friction coefficient [dimensionless]

```

The fluid is air which has the following specific heat ratio.

```

k = 1.4;      % Specific heat ratio [dimensionless]

```

Understanding the Fanno Parameter

The Fanno parameter is a dimensionless quantity that indicates how much influence friction will have while the fluid is flowing through the duct. For a given duct, the Fanno parameter is defined as

$$Fanno\ parameter = \frac{fL}{D_h}$$

Where

$L =$ Length of the duct

$$D_h = \frac{4 * Cross - sectional\ area}{Perimeter\ of\ cross - section} = Hydraulic\ diameter$$

For the circular pipe, assume the hydraulic diameter is the inner diameter of the pipe. The friction coefficient, f , is given by the following expression:

$$f = \frac{4\tau_f}{\frac{1}{2}\rho V^2}$$

where

$\tau_f =$ Shear stress due to wall friction

$\rho =$ Density

$V =$ Velocity

Note, this example uses the convention in which a factor of four is not visible in the Fanno parameter. This convention defines the friction coefficient as four times the skin friction over the dynamic pressure. Friction will have a greater effect on the flow in a long duct than in a short duct because the flow is impeded by more wall surface friction. Additionally, friction is more dominant when the duct is narrow. This is because the boundary layer affects a larger portion of the flow along the walls than when the duct width is large.

Friction is an energy loss that generates entropy (irreversibility) in the system. The increase in entropy causes the flow to tend towards the choked condition (Mach = 1). The choked condition occurs if the length of the duct is long enough. For a given Mach number and specific heat ratio, the reference Fanno parameter for choked flow is

$$\frac{fL_{max}}{D_h} = \frac{1 - M^2}{\gamma M^2} + \frac{\gamma + 1}{2\gamma} \ln \left(\frac{M^2}{\frac{2}{\gamma+1} [1 + \frac{\gamma-1}{2} M^2]} \right)$$

where

$$\gamma = k = \textit{Specific heat ratio}$$

Using the Fanno Parameter and FLOWFANNO to Solve for the Flow Properties at the Inlet

This example provides the length of the duct, the diameter of the duct, and the friction coefficient. Therefore, the actual Fanno parameter of the duct can be computed as follows:

$$\textit{fannoParameter} = \textit{frictionCoeff} * \textit{ductLength} / \textit{diameter};$$

This example also provides the Mach number and specific heat ratio. This enables you to calculate the reference Fanno parameter for the inlet condition, the inlet temperature ratio and inlet the pressure ratio. Use the `flowfanno` function from the Aerospace Toolbox:

$$[\sim, \textit{inletTempRatio}, \textit{inletPresRatio}, \sim, \sim, \sim, \textit{inletFannoRef}] = \textit{flowfanno}(k, \textit{inletMach});$$

$$\textit{inletTempRatio} = \frac{T_1}{T_1^*}$$

$$\textit{inletPresRatio} = \frac{p_1}{p_1^*}$$

$$\textit{inletFannoRef} = \left(\frac{fL_{max}}{D_h} \right)_1$$

where:

- The subscript indicates the flow station.
- Unstarred quantities are the local values of the given variables.
- Starred quantities are referenced value of the given variables if the flow is brought to the choked condition.

The length of the inlet reference Fanno parameter, also called inlet max length, is the length that the pipe needs to be to have choked flow for a given inlet condition. If the actual length is less than the inlet max length, an extension to the pipe is needed for choked flow. This choked flow corresponds to a reference Fanno parameter for the outlet. Since the diameter and friction coefficient are given in the problem statement, only the lengths vary in the following equation for the outlet reference Fanno parameter:

$$\left(\frac{fL_{max}}{D_h} \right)_2 = \left(\frac{fL_{max}}{D_h} \right)_1 - \frac{fL}{D_h}$$

$$\textit{outletFannoRef} = \textit{inletFannoRef} - \textit{fannoParameter};$$

Calculating the Flow Properties at the Outlet with the FLOWFANNO Function

Next, use `flowfanno` to calculate the flow ratios at the outlet station. The third input, 'fannosub', indicates that the second input, `outletFannoRef`, is a subsonic Fanno parameter input.

$$[\textit{outletMach}, \textit{outletTempRatio}, \textit{outletPresRatio}] = \textit{flowfanno}(k, \textit{outletFannoRef}, \textit{'fannosub'});$$

$$\textit{outletTempRatio} = \frac{T_2}{T_2^*}$$

$$\text{outletPresRatio} = \frac{p_2}{p_2^*}$$

Use the temperature ratios found at the inlet and outlet to calculate the temperature and pressure at the outlet. The reference conditions are the same at both stations because the duct is insulated. In addition, assume that the effects of friction act on both stations in the same manner. As a result, we have

$$T_1^* = T_2^*$$

$$p_1^* = p_2^*$$

Therefore, the temperature at the outlet and the pressure at the outlet are

$$T_2 = T_1 \frac{T_1^*}{T_1} \frac{T_2}{T_2^*}$$

```
outletTemperature = inletTemperature / inletTempRatio * outletTempRatio;
```

$$p_2 = p_1 \frac{p_1^*}{p_1} \frac{p_2}{p_2^*}$$

```
outletPressure = inletPressure / inletPresRatio * outletPresRatio;
```

The values that we wanted to calculate are

```
outletMach      % [dimensionless]
outletTemperature % [K]
outletPressure  % [kPa]
```

```
outletMach =
```

```
0.7093
```

```
outletTemperature =
```

```
292.2018
```

```
outletPressure =
```

```
125.2332
```

For Fanno line flow where the inlet flow is subsonic, the temperature and pressure always decrease through the duct. For all Fanno line flow cases the Mach number moves closer to one.

```
close(ductPicture)
```

Reference

[1] James, J. E. A., "Gas Dynamics, Second Edition", Allyn and Bacon, Inc, Boston, 1984.

`%#ok<*NOPTS>`

Determining Heat Transfer and Mass Flow Rate in a Ramjet Combustion Chamber

This example shows how to use the Aerospace Toolbox™ functions to determine heat transfer and mass flow rate in a ramjet combustion chamber.

The Ramjet Engine

When calculating the thrust of a ramjet engine, it is important to optimize the amount of heat added and the mass flow rate through an air breathing engine. This optimization is important because the thrust generated by the engine is governed by these parameters. The ramjet thrust equation is the following:

$$\text{Thrust} = \dot{m}_{\text{exit}}V_{\text{exit}} - \dot{m}_{\text{enter}}V_{\text{enter}} + (p_{\text{exit}} - p_{\text{enter}})A_{\text{exit}}$$

where

$$\dot{m} = \text{Mass flow rate [kg/s]}$$

$$V = \text{Velocity [m/s]}$$

$$p = \text{pressure [kPa]}$$

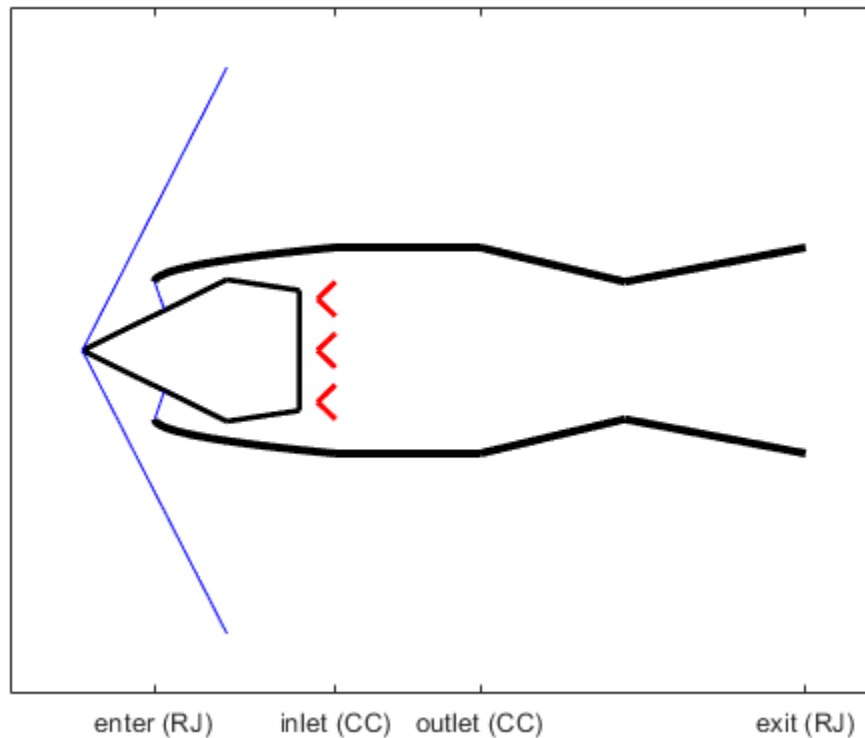
$$A = \text{Cross-sectional area [m}^2\text{]}$$

In the ramjet thrust equation, the subscripts denote the location of the parameter.

- enter - Denotes the entrance of the entire ramjet.
- exit - Denotes the exit of the ramjet engine.
- inlet - Used for the beginning of the combustion chamber.
- outlet - Used for the end of the combustion chamber.

This difference is illustrated in the following figure, (RJ) stands for the entire ramjet engine and (CC) refers to the combustion chamber.

```
ramjetPicture = astramjet;
```



Note, the thrust equation takes directly into account the mass flow rate. Heat addition correlates to higher exit velocity from the energy equation; higher exit velocity means more thrust. Modeling the ramjet combustion chamber as a constant area duct where heat addition is the main driver for the change in the flow variables enables the use of Rayleigh line flow principles.

Problem Definition

This section describes the problem to be solved. It also provides necessary equations and known values.

After a series of shock waves, flow enters the combustion at a velocity of 100 m/s and static temperature of 400K. We want to:

- Maximize the amount of heat added in the combustion chamber without decreasing the mass flow rate.
- Calculate the fuel-air ratio associated with the maximum allowable heat added.

The heating value of the fuel is 40 megajoules per kilogram and the mass of the fuel is negligible compared to the mass of the air. We assume that the working fluid behaves like a perfect gas with constant specific heat ratio and specific heat at constant pressure given as:

$$\gamma = k = \text{Specific heat ratio} = 1.4 \text{ [dimensionless]}$$

$$c_p = \text{Specific heat at constant pressure} = 1.004 \text{ [kJ/(kgK)]}$$

Given data for problem is listed below.


```

inletVelocity      = 100;      % Velocity of fluid at combustor intake [m/s]
inletTemperature  = 400;      % Temperature of fluid at combustor intake [K]
heatingValue      = 40e+03;   % Heating value of the fuel [kJ/kg]
k                 = 1.4;      % Specific heat ratio [dimensionless]
cp                = 1.004;    % Specific heat at constant pressure [kJ/(kg*K)]
    
```

Because the fluid is air, it also has the following gas constant:

```
R = 287; % Gas constant of air [J/(kg*K)]
```

Therefore, the speed of sound is:

```
speedOfSound = sqrt(k * R * inletTemperature); % [m/s]
```

The inlet Mach number is

```
inletMach = inletVelocity/speedOfSound; % [dimensionless]
```

Solving for the Stagnation Quantities and Reference Values

To apply the energy equation in order to find the heat transfer rate, calculate the stagnation temperature at the inlet. Use isentropic flow ratios and the static temperature at that point to calculate this temperature. The `flowisentropic` function calculates the ratio of the static temperature to the total (stagnation) temperature.

$$\frac{T_{inlet}}{T_{inlet}} = inletTempRatio$$

Where

$$T_{t_{inlet}} = Total\ temperature\ (at\ the\ inlet)$$

```
[~, inletTempRatio, inletPresRatio] = flowisentropic(k, inletMach);
```

With the temperature ratio at the inlet, calculate the total temperature at the inlet. Be careful. Note that the form in which we need the temperature ratio is inverted from the form as given in the `flowisentropic` function.

$$T_{t_{inlet}} = T_{inlet} \frac{T_{inlet}}{T_{inlet}}$$

```
inletTotalTemp = inletTemperature / inletTempRatio;
```

Use the energy equation to describe the flow in the combustion chamber:

$$\dot{q} = \dot{m}_{air} c_p (T_{t_{outlet}} - T_{t_{inlet}}) = \dot{m}_{fuel} * heatingValue$$

where

$$\dot{q} = rate\ of\ heat\ transfer\ [kW]$$

To maximize the rate of heat transfer, the stagnation temperature at the outlet station must be the reference stagnation temperature:

$$T_{t_{outlet}} = T_t^*$$

Use the `flowrayleigh` function to calculate the total temperature ratio at the inlet. After this, you can calculate the reference total temperature.

```
[~,~,~,~,~,totalTempRatio] = flowrayleigh(k, inletMach);
```

In this equation, note that this ratio is found by the function as the local value over the reference value.

$$\frac{T_{t_{inlet}}}{T_t^*} = totalTempRatio$$

Now calculate the reference total temperature. Note that the total temperature ratio has been inverted to allow the proper cancellation of terms.

$$T_t^* = T_{t_{inlet}} \frac{T_t^*}{T_{t_{inlet}}}$$

```
inletTotalTempRef = inletTotalTemp / totalTempRatio;
```

Calculating the Fuel-to-Air Ratio and Maximum Heat Added

Calculate the fuel-to-air ratio by rearranging the energy equation.

$$\frac{\dot{m}_{fuel}}{\dot{m}_{air}} = \frac{c_p(T_t^* - T_{t_{inlet}})}{heatingValue}$$

```
fuelAirRatio = cp * (inletTotalTempRef - inletTotalTemp) / heatingValue
```

```
fuelAirRatio =
```

```
0.0296
```

The maximum heat added is:

$$q_{max} = c_p * (T_t^* - T_{t_{inlet}})$$

```
heatMax = cp * (inletTotalTempRef - inletTotalTemp)
```

```
heatMax =
```

```
1.1826e+03
```

Accounting for an Increase in the Fuel-Air Ratio

Consider the case where there is a 10% increase in the fuel-air ratio. Calculate how much the mass flow rate decreases with a 10% increase in fuel-to-air ratio, holding the stagnation temperature and pressure constant. The new fuel-air ratio is:

```
fuelAirRatio10 = 1.1 * fuelAirRatio;
```

Note, any variable that ends with "10" indicate that the given value is related to the 10% increase in fuel-to-air ratio. Rearrange the energy equation to calculate the difference in total temperatures from the inlet to the outlet of the combustion chamber:

$$T_{t_{outlet}} - T_{t_{inlet}} = \frac{\dot{m}_{fuel} * heatingValue}{\dot{m}_{air} c_p}$$

totalTempDiff = fuelAirRatio10 * heatingValue / cp;

The maximum heating condition is where the flow is choked at the outlet:

$$T_{t_{outlet}} = T_t^*$$

Therefore, inlet reference total temperature and the ratio of total temperature to the reference value are:

$$T_{t_{inlet}}^* = T_{t_{outlet}} - T_{t_{inlet}} + T_t^*$$

$$\frac{T_{t_{inlet}}}{T_{t_{inlet}}^*} = totalTempRatio$$

inletTotalTempRef10 = totalTempDiff + inletTotalTemp;

totalTempRatio10 = inletTotalTemp / inletTotalTempRef10;

Calculating the Decrease in Mass Flow Rate

Given the total temperature ratio, flowrayleigh calculates the Mach number at the inlet of the combustion chamber:

inletMach10 = flowrayleigh(k, totalTempRatio10, 'totaltsub');

In this equation, the string input causes the function to use the subsonic total temperature ratio input mode. We know that the flow will be subsonic entering the combustion chamber because the flow will have gone through several shock waves leading up to the combustion chamber. With this Mach number at the inlet, use flowisentropic to find the isentropic temperature ratio and pressure ratio at the inlet:

[~, inletTempRatio10, inletPresRatio10] = flowisentropic(k, inletMach10);

The static temperature at the inlet is:

inletTemperature10 = inletTotalTemp * inletTempRatio10;

From the equation of state, the mass flow rate can be written as:

$$\dot{m} = \frac{P}{RT} A(M \sqrt{\gamma RT})$$

With a 10% fuel-air ratio increase, relate a ratio showing a decrease in mass flow from a 10% increase in the mass flow rate to the ratio of decreasing Mach number. The increase in pressure ratio contributes to increasing the mass flow rate, but not as much as the decrease in Mach number decreases the mass flow rate. All other variables are constant between the two cases.

$$\frac{\dot{m}_{10}}{\dot{m}} = \frac{M_{10}}{M} \left(\frac{P_{inlet}}{P_{inlet}} \right)_{10}$$

```
massFlowRateRatio = inletMach10 / inletMach * inletPresRatio10 / inletPresRatio;
```

This ratio represents the percentage of the mass flow rate of the case with a 10% increase in fuel-to-air ratio. It uses the original mass flow rate as a whole. The percentage decrease in mass flow rate is just one minus the above ratio (times 100):

```
percentageDecrease = ( 1 - massFlowRateRatio ) * 100 % [percent]
```

```
percentageDecrease =
```

```
3.7665
```

These results show that adding fuel to the fuel-air mixture decreases the mass flow rate. This in turn makes the thrust decrease. This means that once a certain amount of fuel is added to the combustion chamber, adding more produces an inefficient result. Therefore, preemptive calculations such as these help engineers maximize fuel efficiency around the design conditions of an engine.

```
close(ramjetPicture)
```

Reference

[1] James, J. E. A., "Gas Dynamics, Second Edition", Allyn and Bacon, Inc, Boston, 1984.

```
 %#ok<*NOPTS>
```

Solving for the Exit Flow of a Supersonic Nozzle

This example shows how to use the method of characteristics and Prandtl-Meyer flow theory to solve a problem in supersonic flow involving expansions. Solve for the flow field downstream of the exit of a supersonic nozzle.

Problem Definition

This section describes the problem to be solved. It also provides necessary equations and known values.

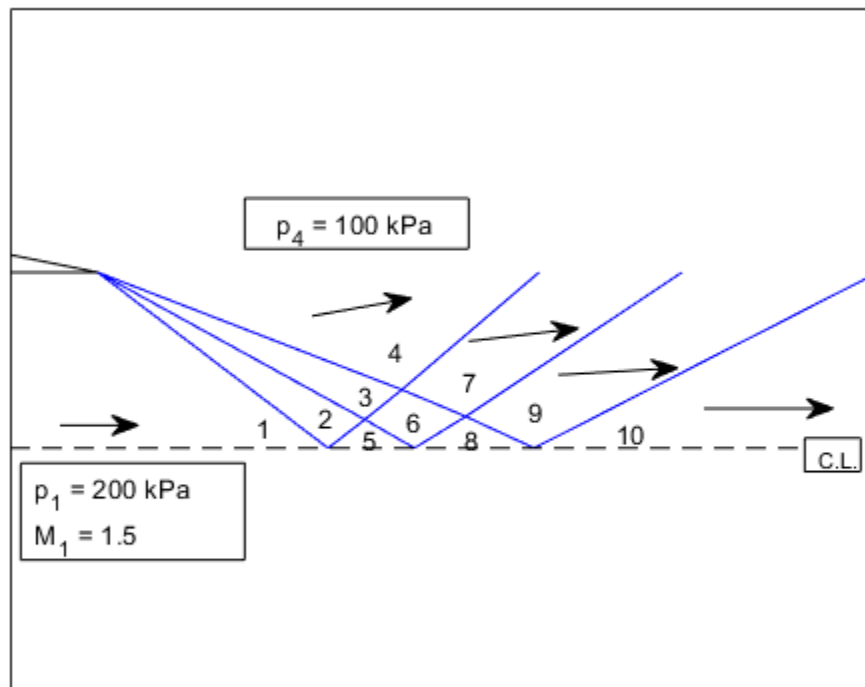
Solve for the flow field downstream of a supersonic nozzle using the method of characteristics. The Mach number at the exit plane is 1.5 and the pressure at the exit plane is 200 kilopascals. The back pressure is 100 kilopascals.

Assumptions:

- Flow is isentropic
- Variation in flow properties depend on the interaction of expansion waves that occur throughout the wake of the nozzle.
- The geometry of the nozzle and the flow is symmetric.

Model the expansion fan as three characteristics. Due to symmetry, arbitrarily choose to work only on the top half of the flow. Following is a figure of the nozzle exit.

```
upperNozzle = astexpandschematic('uppernozzle');
```



The given information in the problem is:

```
exitMach = 1.5; % Mach number at the exit plane [dimensionless]
exitPres = 200; % Static pressure at the exit plane [kPa]
backPres = 100; % Pressure downstream of the nozzle, outside of the expansion wake
```

The fluid is assumed to be air that behaves like a perfect gas with the following constant specific heat ratio.

```
k = 1.4; % Specific heat ratio [dimensionless]
```

Method of Characteristics

The method of characteristics is a theory for supersonic flow that analyzes the irrotational potential flow equation in fully nonlinear form. Isentropic flow is assumed. The definition of characteristics are the curves in the flow where the velocity is continuous but the first derivative of velocity is discontinuous.

In the previous figure, the blue lines in the are approximate characteristics. Characteristics of type I make a negative acute angle with the flow direction. Characteristics of type II make a positive acute angle with the flow direction. A detailed derivation of the method is outside the scope of this example analysis. This example analysis uses the region-to-region procedure. It is assumed that you are familiar with this procedure.

In Prandtl-Meyer flow and the method of characteristics, calculate the important angles for all regions of the flow.

- Flow angle is the direction in which the air is moving.

$$\theta_n = \text{Flow angle in the } n^{\text{th}} \text{ region}$$

- The Prandtl-Meyer angle is the angle at which the flow changes direction from one region to another.

$$\nu_n = \text{Prandtl - Meyer angle in the } n^{\text{th}} \text{ region}$$

- Mach angle is the angle between the local flow direction and the weak pressure waves that emanate from a given point.

$$\mu_n = \text{Mach angle in the } n^{\text{th}} \text{ region}$$

Compute the Mach number in each region and solve for the angles of both types of characteristic in all of the regions. Solve for the geometric boundary of all of the regions by calculating the slopes of all of the characteristics and locate of all of the intersections of characteristics.

Computing the Flow Properties Through the First Expansion Fan

Determine the Mach number outside the wake (region 4). The Mach number at this location can be found using isentropic ratios for pressure and the given values for pressure. The pressure ratio at the exit plane is easily solved for using `flowisentropic`.

```
[~, ~, exitPresRatio] = flowisentropic(k, exitMach);
```

The back pressure ratio is the ratio of the back pressure to the stagnation pressure. The isentropic pressure ratio at the outer wake region is:

$$\frac{p_4}{p_0} = \frac{p_4}{p_1} \frac{p_1}{p_0}$$

```
backPresRatio = backPres / exitPres * exitPresRatio;
```

Calculate the Mach number in region 4 using `flowisentropic`.

```
backMach = flowisentropic(k, backPresRatio, 'pres');
```

The 'pres' string input indicates that the function is in pressure ratio input mode. The flow angle in the back pressure region is the difference in Prandtl-Meyer angles from the exit plane region (region 1) to the back pressure region (region 4).

$$\theta_4 = \nu_4 - \nu_1$$

```
[~, nu_1] = flowprandtlmeyer(k, exitMach);
```

```
[~, nu_4] = flowprandtlmeyer(k, backMach);
```

```
theta_4 = nu_4 - nu_1;
```

Because we are approximating the flow with three characteristics, we calculate the change in flow angle in crossing type I characteristics from region 1 to region 4:

$$\Delta\theta_I = \frac{\theta_4}{3}$$

```
deltaThetaI = theta_4 / 3;
```

Note that flow in region 1 is parallel to the horizontal and therefore:

```
theta_1 = 0;
```

In fact, the flow in any region that straddles the centerline is parallel to the centerline. This is because the centerline is considered to be a boundary for this symmetric flow. In addition, there are no sources nor sinks at the boundary.

```
theta_5 = 0;
```

```
theta_8 = 0;
```

```
theta_10 = 0;
```

The flow angles of regions 2 and 3 follow simply.

```
theta_2 = theta_1 + deltaThetaI;
```

```
theta_3 = theta_2 + deltaThetaI;
```

Across type I characteristics, the change in Prandtl-Meyer angle is equal to the change in flow angle:

$$\Delta\nu_I = \Delta\theta_I$$

```
deltaNuI = deltaThetaI;
```

Calculate the Prandtl-Meyer angle in region 2 by using the Prandtl-Meyer angle in region 1 and `deltaNuI`, the change in Prandtl-Meyer angle through type I characteristics. Calculate the Prandtl-Meyer angle in region 3 in a similar manner to that of region 2.

$$\Delta\nu_I = \nu_2 - \nu_1$$

$$\nu_2 = \nu_1 + \Delta\nu_I$$

```
nu_2 = nu_1 + deltaNuI;
nu_3 = nu_2 + deltaNuI;
```

Calculating Flow Properties in the Interference Regions

The flow angle in region 5 is known to be zero from the centerline boundary condition. Therefore, the change in angle from region 2 to region 5 is

$$\Delta\theta_{II} = \theta_5 - \theta_2$$

```
deltaThetaII = theta_5 - theta_2;
```

Calculate the change in Prandtl-Meyer angle across type II characteristics:

$$\Delta\nu_{II} = -\Delta\theta_{II}$$

```
deltaNuII = -deltaThetaII;
```

Then, calculate the Prandtl-Meyer angle in region 5. You already know the region 2 Prandtl-Meyer angle and the change in Prandtl-Meyer angle across type II characteristics.

```
nu_5 = nu_2 + deltaNuII;
```

To calculate the properties in region 6, use the fact that the properties in region 3 and region 5 are known. Note also that which characteristic the flow crosses define the changes in properties. From region 5 to region 6, a type I characteristic is crossed. Therefore,

$$\Delta\theta_I = \Delta\nu_I = \theta_6 - \theta_5 = \nu_6 - \nu_5$$

Rearranged this as:

$$\nu_6 - \theta_6 = \nu_5 - \theta_5 \quad (1)$$

A type II characteristic is crossed in going from region 3 to region 6. Therefore,

$$\Delta\nu_{II} = -\Delta\theta_{II}$$

$$\nu_6 - \nu_3 = \theta_3 - \theta_6$$

Rearranging this as:

$$\nu_6 + \theta_6 = \nu_3 + \theta_3 \quad (2)$$

Add equations (1) and (2) together, then solve for the Prandtl-Meyer angle in region 6. This yields the following expression.

$$\nu_6 = \frac{(\nu_5 - \theta_5) + (\nu_3 + \theta_3)}{2}$$

In MATLAB®, use:

```
nu_6 = ((nu_5 - theta_5) + (nu_3 + theta_3))/2;
```

From equation (1), the flow angle in region 6 is

```
theta_6 = nu_6 - (nu_5 - theta_5);
```


For region 7 a type one characteristic is crossed and all information is available in region 6.

$$\begin{aligned} \text{nu}_7 &= \text{nu}_6 + \text{deltaNuI}; \\ \text{theta}_7 &= \text{theta}_6 + \text{deltaThetaI}; \end{aligned}$$

Region 8 is on the centerline; its flow angle is zero. Going from region 6 to region 8 requires crossing a type II characteristic. Therefore, calculate the Prandtl-Meyer angle in region 8 as:

$$\text{nu}_8 = \text{nu}_6 + \text{deltaNuII};$$

Calculate the Prandtl-Meyer angle and flow angle in region 9 just like the way you did for region 6. Region 8 is the upstream region across the type I characteristic. Region 7 is the upstream region across the type II characteristic.

$$\begin{aligned} \text{nu}_9 &= ((\text{nu}_8 - \text{theta}_8) + (\text{nu}_7 + \text{theta}_7))/2; \\ \text{theta}_9 &= \text{nu}_9 - (\text{nu}_8 - \text{theta}_8); \end{aligned}$$

Region ten is on the centerline. The flow is parallel and so the flow angle is zero. Use the Prandtl-Meyer angle in region 9 and the crossing over a type II characteristic to calculate the Prandtl-Meyer angle in region 10.

$$\text{nu}_{10} = \text{nu}_9 + \text{deltaNuII};$$

Preparing and Tabulating the Flow Parameter Results

For upcoming calculations, combine the flow angles into one vector and the Prandtl-Meyer angles into another vector.

$$\begin{aligned} \text{flowAngles} &= [\text{theta}_1 \text{ theta}_2 \text{ theta}_3 \text{ theta}_4 \text{ theta}_5 \text{ theta}_6 \text{ theta}_7 \text{ theta}_8 \text{ theta}_9 \text{ theta}_{10}]; \\ \text{prandtlMeyerAngles} &= [\text{nu}_1 \text{ nu}_2 \text{ nu}_3 \text{ nu}_4 \text{ nu}_5 \text{ nu}_6 \text{ nu}_7 \text{ nu}_8 \text{ nu}_9 \text{ nu}_{10}]; \end{aligned}$$

To calculate the Mach numbers and Mach angles in each region, using the `flowprandtlmeyer` function with the `prandtlMeyerAngles` as the input. You can use the results from this function to find the angle that the type I and type II characteristics make with the horizontal inside each region. You can then use these angles to calculate slopes in the x-y plane, where the centerline is the x-axis and the exit plane of the nozzle is the y-axis. For type I characteristics and type II characteristics, respectively, the slopes are:

$$\left(\frac{dy}{dx}\right)_I = \tan(\theta - \mu)$$

$$\left(\frac{dy}{dx}\right)_{II} = \tan(\theta + \mu)$$

Note, the values in the following table for type I and type II are the angles with the horizontal, not the slopes.

```
% Preallocation for speed
machNumbers = zeros(1,10);
machAngles = zeros(1,10);
typeOne = zeros(1,10);
typeTwo = zeros(1,10);

for i = 1:10
    [machNumbers(i), ~, machAngles(i)] = flowprandtlmeyer(k, prandtlMeyerAngles(i), 'nu');
```

```

    typeOne(i) = flowAngles(i) - machAngles(i);
    typeTwo(i) = flowAngles(i) + machAngles(i);
end

clear table;
table(1,:) = 'Region   theta       nu       Mach       mu       type I   type II';
table(2,:) = '          (Deg)     (Deg)           (Deg)     (Deg)     (Deg)   (Deg)   ';
for m=1:length(machNumbers)
table(m+3,:) = sprintf('%3.0d   %8.2f       %5.2f   %8.3f   %8.2f   %8.2f   %8.2f ', ...
    m, flowAngles(m), prandtlMeyerAngles(m), machNumbers(m), ...
    machAngles(m), typeOne(m), typeTwo(m));
end

disp(table)

```

Region	theta (Deg)	nu (Deg)	Mach	mu (Deg)	type I (Deg)	type II (Deg)
1	0.00	11.91	1.500	41.81	-41.81	41.81
2	4.45	16.35	1.650	37.29	-32.85	41.74
3	8.89	20.80	1.803	33.70	-24.80	42.59
4	13.34	25.24	1.959	30.69	-17.35	44.03
5	0.00	20.80	1.803	33.70	-33.70	33.70
6	4.45	25.24	1.959	30.69	-26.25	35.14
7	8.89	29.69	2.122	28.11	-19.22	37.00
8	0.00	29.69	2.122	28.11	-28.11	28.11
9	4.45	34.14	2.294	25.84	-21.40	30.29
10	0.00	38.58	2.477	23.81	-23.81	23.81

Note the following:

- The flow angles increase away from the centerline.
- The Prandtl-Meyer angles increase as the flow moves downstream.
- The Mach number also increases as the flow moves downstream.

Solving for the Flow Geometry

The flow properties are known in all regions, but in order to solve for the flow field you must calculate the actual geometry of each region. The last two columns of the above table contain the angles that each type of characteristic makes with the horizontal. Because straight lines approximate the characteristics of the flow in each region, the boundary between any two regions is approximated by the average of the angles that each makes in the bordering regions. Because the waves bend through the expansion fan, begin the analysis from the point from which the characteristics originate. The characteristics originate at the lip of the nozzle and work downstream.

Assume the intersection of the centerline and the exit plane of the nozzle is the origin of our coordinate system. Also assume lengths are normalized to half of the exit height of the nozzle. The positive x axis is taken horizontal along the centerline in the downstream direction. The positive y axis is vertically up in the exit plane of the nozzle. The lip of the nozzle is at the point (0,1).

All three characteristics that propagate from the upper lip are type I characteristics. Analyze the steepest sloping characteristic first because no waves interfere with the steepest wave until the steepest wave intersects the centerline. In the symmetric half-nozzle model, the steepest wave reflects back into the fan and interferes with the other waves in the expansion fan.

This wave that "reflects" from the centerline is actually the steepest sloping type II characteristic that propagates from the bottom lip. However, the analysis considers the centerline to be a boundary due to symmetry. This produces the same results that you would get if you worked both halves of the nozzle.

The steepest sloping line from the lip is a type I characteristic that separates region 1 and region 2. To calculate the angle that steepest sloping wave makes with the horizontal use the average of angles that the type I characteristics make in each region. To calculate the slope use trigonometry.

```
avgAngle12 = (typeOne(1) + typeOne(2)) / 2;
slope12    = tand(avgAngle12);
```

With the following information known:

- Slope of the first type I wave in x-y space.
- The y-intercept of the wave (y = 1 at the lip).
- The wave intersects the centerline (y = 0) without interference.

Calculate the x-location of the point using the equation of a line in slope-intercept form. Rearrange $y = m*x+b$ for the x-location with $y = 0$ to produce $x = -b / m$. This is the x-location of the first downstream point, point 1.

```
y1 = 0; % On the centerline
x1 = -1 / slope12;
```

From point 1, the first type II characteristic propagates and interferes with the fan. The other type I characteristics that originate from the nozzle lip are disturbed by the type II wave, but not before reaching that wave. Therefore, calculate the points of intersection of the steepest type II characteristic and the flatter type I waves from the lip. The type II characteristic coming up from the centerline separates region 2 and region 5. The average of the two angles and associated slopes are given by:

```
avgAngle25 = (typeTwo(2) + typeTwo(5)) / 2;
slope25    = tand(avgAngle25);
```

The second steepest type I characteristic is the from the nozzle lip, separates region 2 and region 3. The average angle with the horizontal and the associated slope of the wave are given by:

```
avgAngle23 = (typeOne(2) + typeOne(3)) / 2;
slope23    = tand(avgAngle23);
```

Calculate the point of intersection of the region 2-3 boundary and the region 2-5 boundary. You need this point because the characteristics interfere with each other at this point. The slopes of both boundaries and a point on each line are known. Point 1 and the nozzle lip (to be referenced point 0 are known." Solve for the unknown x-coordinate of the point of intersection. Use that x-location in the equation of either of the two lines to find the y-location of the point of intersection. The point-slope form equation of a line through point p with slope m is:

$$y - y_p = m(x - x_p)$$

The advantage of this form of a line is that you need only one point and the slope to completely define the line. The x and y without subscripts can be any point on the line. However, the point of intersection of two lines must be unique. Calling this point of intersection point 2, the equation of both lines are the following.

$$y_2 - y_0 = m_{2,3}(x_2 - x_0) \quad (3)$$

$$y_2 - y_1 = m_{2,5}(x_2 - x_1) \quad (4)$$

where

$$m_{i,j} = \text{Slope of the boundary between region } i \text{ and region } j$$

Subtract and rearrange:

$$x_2 = \frac{x_1 m_{2,5} - x_0 m_{2,3} + y_0 - y_1}{m_{2,5} - m_{2,3}}$$

Knowing some of the values exactly due to the axes intercepts simplifies this expression to.

$$x_2 = (x_1 * \text{slope}_{25} + 1) / (\text{slope}_{25} - \text{slope}_{23});$$

Below the y-location of point 2 is found by plugging the x-location of point 2 into equation (4) above, but plugging into equation (3) works just as well.

$$y_2 = (x_2 - x_1) * \text{slope}_{25};$$

Use the slope-intercept formula and the procedure above to calculate all points. To calculate the third point in the flow, first calculate the intersection of the region 3-4 boundary and the 3-6 boundary. The angles of the boundary lines are calculated using the average of the angles with the horizontal. You can then use trigonometry to find the slope, which is now computed in one step.

$$\begin{aligned} \text{slope}_{34} &= \text{tand}(\text{typeOne}(3) + \text{typeOne}(4)) / 2); \\ \text{slope}_{36} &= \text{tand}(\text{typeTwo}(3) + \text{typeTwo}(6)) / 2); \end{aligned}$$

Because the boundary between region 3 and region 4 is a type I characteristic and the boundary between region 3 and region 6 is a type II characteristic, be careful to take the angles for the appropriate type. Use the point-slope form of these boundary lines subtracted from each other to calculate the x-location of point 3.

$$\begin{aligned} x_3 &= (y_2 - 1 - x_2 * \text{slope}_{36}) / (\text{slope}_{34} - \text{slope}_{36}); \\ y_3 &= (x_3 - x_2) * \text{slope}_{36} + y_2; \end{aligned}$$

The first type II characteristic now propagates beyond the fan and does not interfere with any other characteristics. The angle that defines the direction in which the steepest type II propagates is an angle which is the average of type II waves in regions 4 and 7.

$$\text{slope}_{47} = \text{tand}(\text{typeTwo}(4) + \text{typeTwo}(7)) / 2);$$

Solve also the second steepest type I characteristic to continue downstream. Start from the known location of point 2 to calculate the x-intercept of the second type I characteristic. Again, the solution uses the point-slope form of the line. However, there is no interference until the centerline boundary is reached. We only need to consider one line to find the x-location of "point 4". The slope of the boundary between region 5 and region 6 is a type I wave:

$$\text{slope}_{56} = \text{tand}(\text{typeOne}(5) + \text{typeOne}(6)) / 2);$$

The rearranged point-slope form (knowing $y = 0$ at the centerline) is used to find point 4.

$$\begin{aligned} x_4 &= (\text{slope}_{56} * x_2 - y_2) / \text{slope}_{56}; \\ y_4 &= 0; \end{aligned}$$

Calculate point 5 in the same manner as point 2. The region 6-7 boundary is type I and the region 6-8 boundary is type II.

```
slope67 = tand( ( typeOne(6) + typeOne(7)) / 2);
slope68 = tand( (typeTwo(6) + typeTwo(8)) / 2);
```

The known point on the region 6-7 boundary is point 3. The known point on the region 6-8 boundary is point 4. Use this information in the slope-intercept form, subtracting the equations, and rearrange to yield the location of the next point.

```
x5 = (-x4 * slope68 + x3 * slope67 + y4 - y3) / (slope67 - slope68);
y5 = (x5 - x4) * slope68 + y4;
```

The second type II characteristic propagates beyond the fan at an angle averaged between the region 7 and region 9 angles for type II waves.

```
slope79 = tand( (typeTwo(7) + typeTwo(9)) / 2);
```

The last point of interest is the x-intercept of the flattest type I wave. Calculate this point by knowing the location of point 5 and finding the slope of the type I wave between region 8 and region 9.

```
slope89 = tand( (typeOne(8) + typeOne(9)) / 2);
y6      = 0;
x6      = (slope89 * x5 - y5) / slope89;
```

The final type II wave propagates away at an angle averaged between region 9 and region 10.

```
slope910 = tand( (typeTwo(9) + typeTwo(10)) / 2);
```

With all the points calculated and the slope of the freely propagating lines known, connect the dots:

```
points = astexpandschematic('nozzlepoints');
```


Visualizing World Magnetic Model Contours for 2015v2 Epoch

This example shows how to visualize contour plots of the calculated values for the Earth's magnetic field using World Magnetic Model 2015v2 (WMM2015v2) overlaid on maps of the Earth. WMM2015v2, released by NOAA in February of 2019, addresses degraded performance of WMM2015(v1) in the Arctic region and supersedes it. For more information about the WMM2015v2 release, see <https://www.ncei.noaa.gov/news/world-magnetic-model-out-cycle-release>.

The Mapping Toolbox™ is required to generate the maps of the Earth.

Generating Values for Earth's Magnetic Field

Calculate values for the Earth's magnetic field using `wrldmagm` function to implement the World Magnetic Model 2015v2 (WMM2015v2):

- X - North component of magnetic field vector in nanotesla (nT)
- Y - East component of magnetic field vector in nanotesla (nT)
- Z - Down component of magnetic field vector in nanotesla (nT)
- H - Horizontal intensity in nanotesla (nT)
- DEC - Declination in degrees
- DIP - Inclination in degrees
- F - Total intensity in nanotesla (nT)

Based on the `wrldmagm` inputs:

- `model_epoch` - Epoch of WMM model.
- `decimal_year` - Scalar value representing the decimal year within the epoch for which the data was generated.

```
model_epoch = '2015v2';
decimal_year = 2015;
```

For a given epoch and decimal year, use the following code to generate 13021 data points for calculating values of Earth's magnetic field using `wrldmagm`. To reduce overhead calculation, this model includes a mat-file that contains this data for epoch 2015v2 and decimal year 2015.

```
% % Assume zero height
% height = 0;
%
% % Geodetic Longitude value in degrees to use for latitude sweep.
% geod_lon = -180:1:180;      %degrees
%
% % Geodetic Latitude values to sweep.
% geod_lat = -89.5:.5:89.5;   %degrees
%
% % Loop through longitude values for each array of latitudes -89.5:89.5.
% for lonIdx = size(geod_lon,2):-1:1
%     for latIdx = size(geod_lat,2):-1:1
%
%         % Use WRLDMAGM function to obtain magnetic parameters for each lat/lon
%         % value.
%         [xyz, h, dec, dip, f] = wrldmagm(height, geod_lat(latIdx),geod_lon(lonIdx), decimal_year, r
```

```
% % Store results
% WMMResults(latIdx,1:7,lonIdx) = [xyz' h dec dip f];
%
% end
% end
```

Load data saved in mat-file.

```
WMMFileName = 'WMMResults_Epoch_2015v2_decyear_2015.mat';
load(WMMFileName);
```

Read in continent land areas for plot overlay using Mapping Toolbox function, shaperead.

```
landAreas = shaperead('landareas.shp','UseGeoCoords',true);
```

Plotting Earth's Magnetic Field Overlaid on Earth Maps

Load plot formatting data for each of the magnetic parameters.

```
plotWMM = load('astPlotWMM.mat');
```

```
hX = figure;
```

```
set(hX,'Position',[0 0 827 620],'Color','white')
```

```
astPlotWMMContours(WMMResults, plotWMM, 1, landAreas, geod_lat, geod_lon, decimal_year, model_ep
```

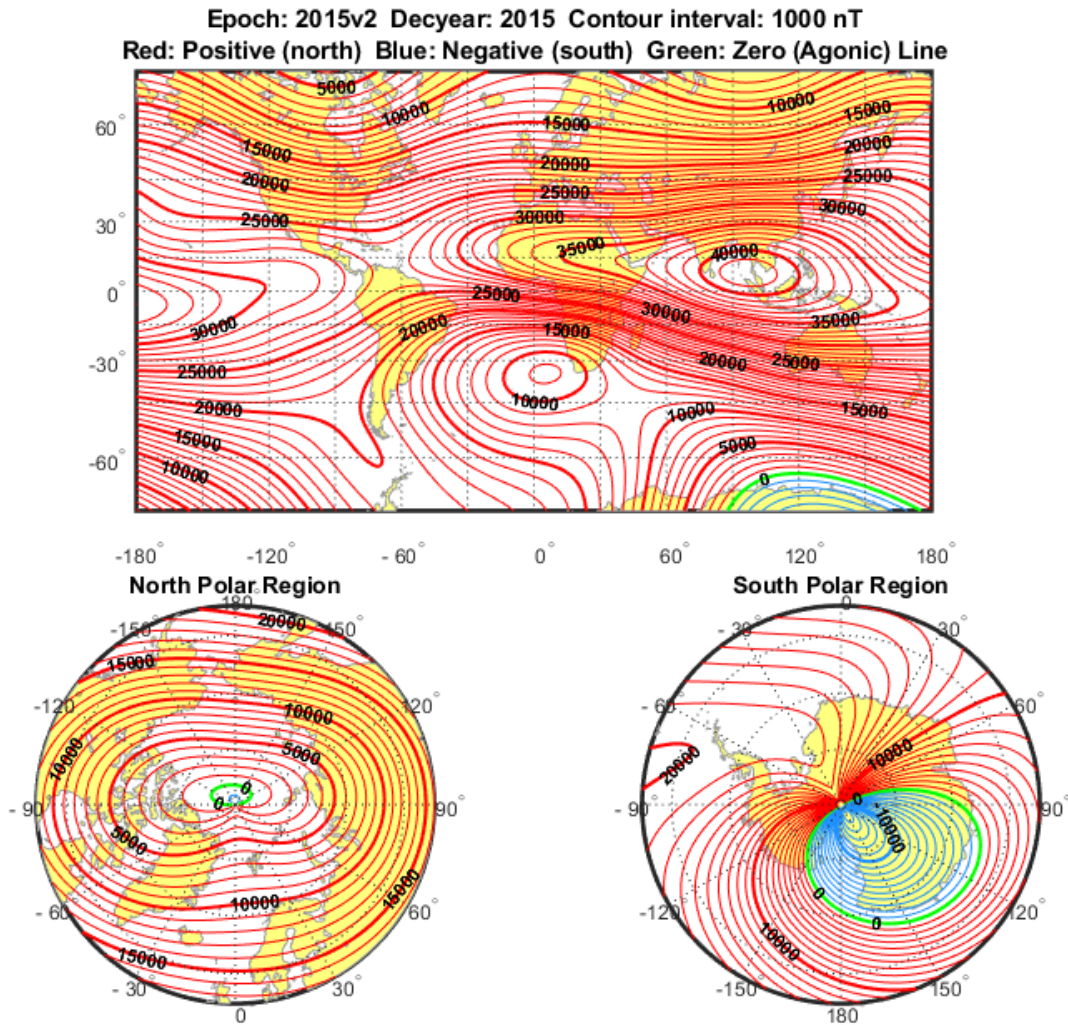



Figure 1: North Component of Magnetic Field Vector, X (nT)

```

hY = figure;
set(hY,'Position',[0 0 827 620],'Color','white')
astPlotWMMContours( WMMResults, plotWMM, 2, landAreas, geod_lat, geod_lon, decimal_year, model_ep

```

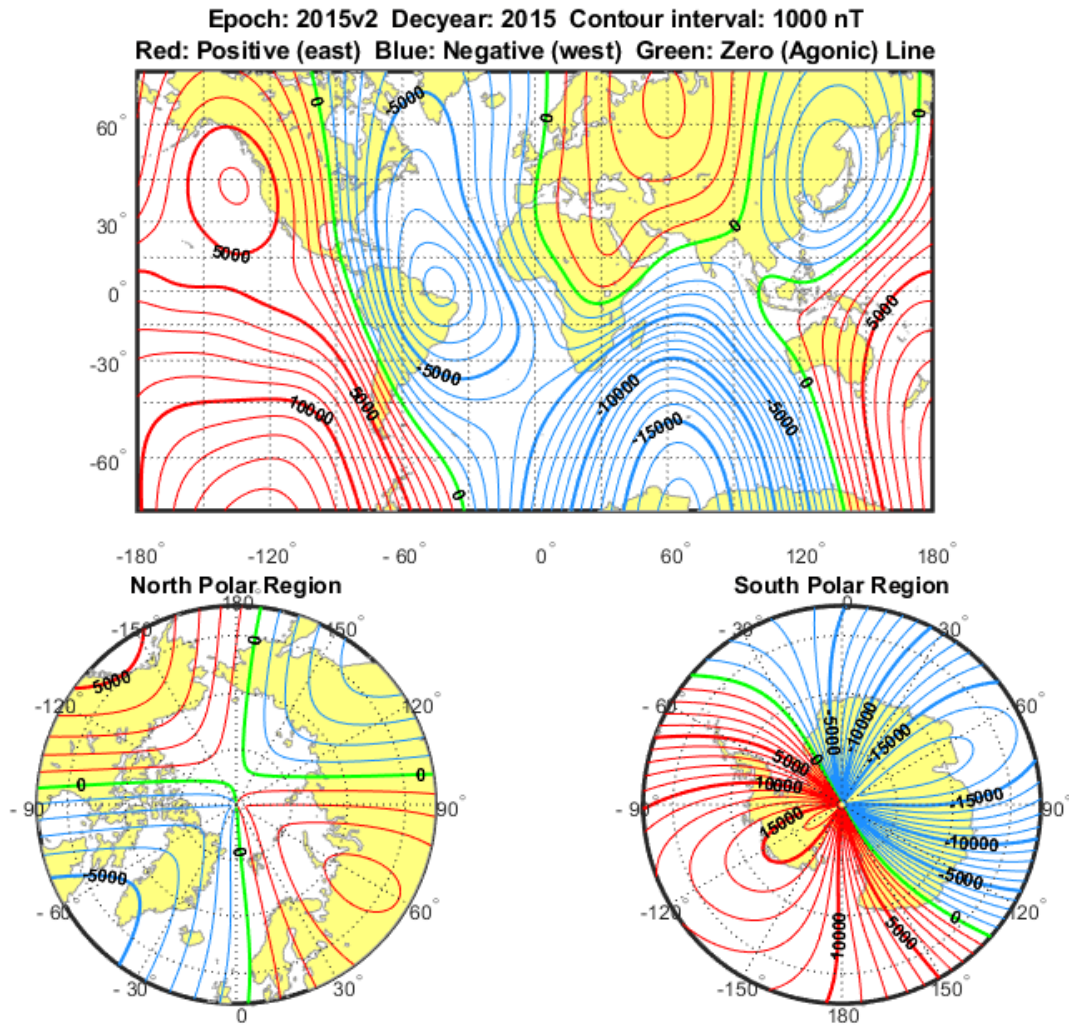


Figure 2: East Component of Magnetic Field Vector, Y (nT)

```
hZ = figure;
set(hZ, 'Position', [0 0 827 620], 'Color', 'white')
astPlotWMMContours( WMMResults, plotWMM, 3, landAreas, geod_lat, geod_lon, decimal_year, model_ep
```

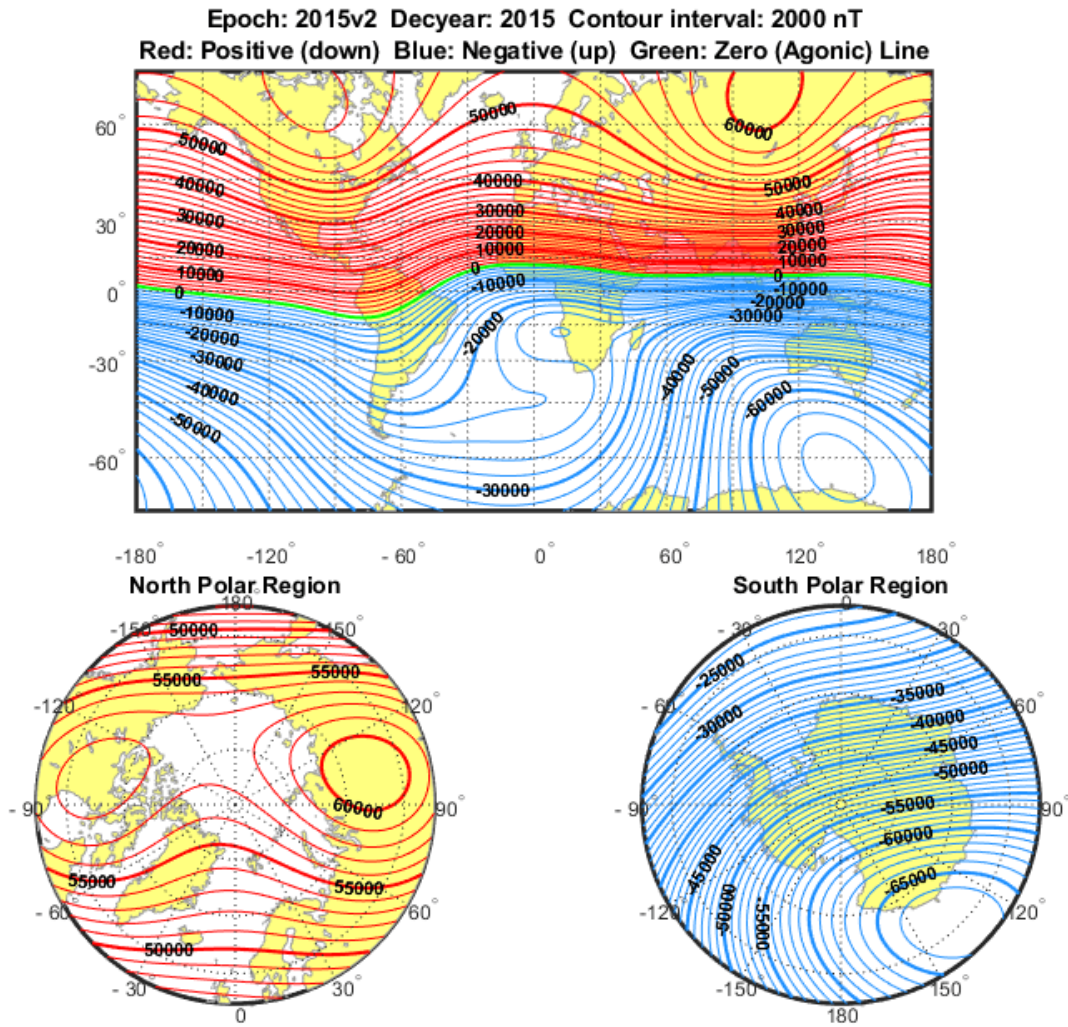


Figure 3: Down Component of Magnetic Field Vector, Z (nT)

```

hH = figure;
set(hH, 'Position', [0 0 827 620], 'Color', 'white')
astPlotWMMContours( WMMResults, plotWMM, 4, landAreas, geod_lat, geod_lon, decimal_year, model_ep

```

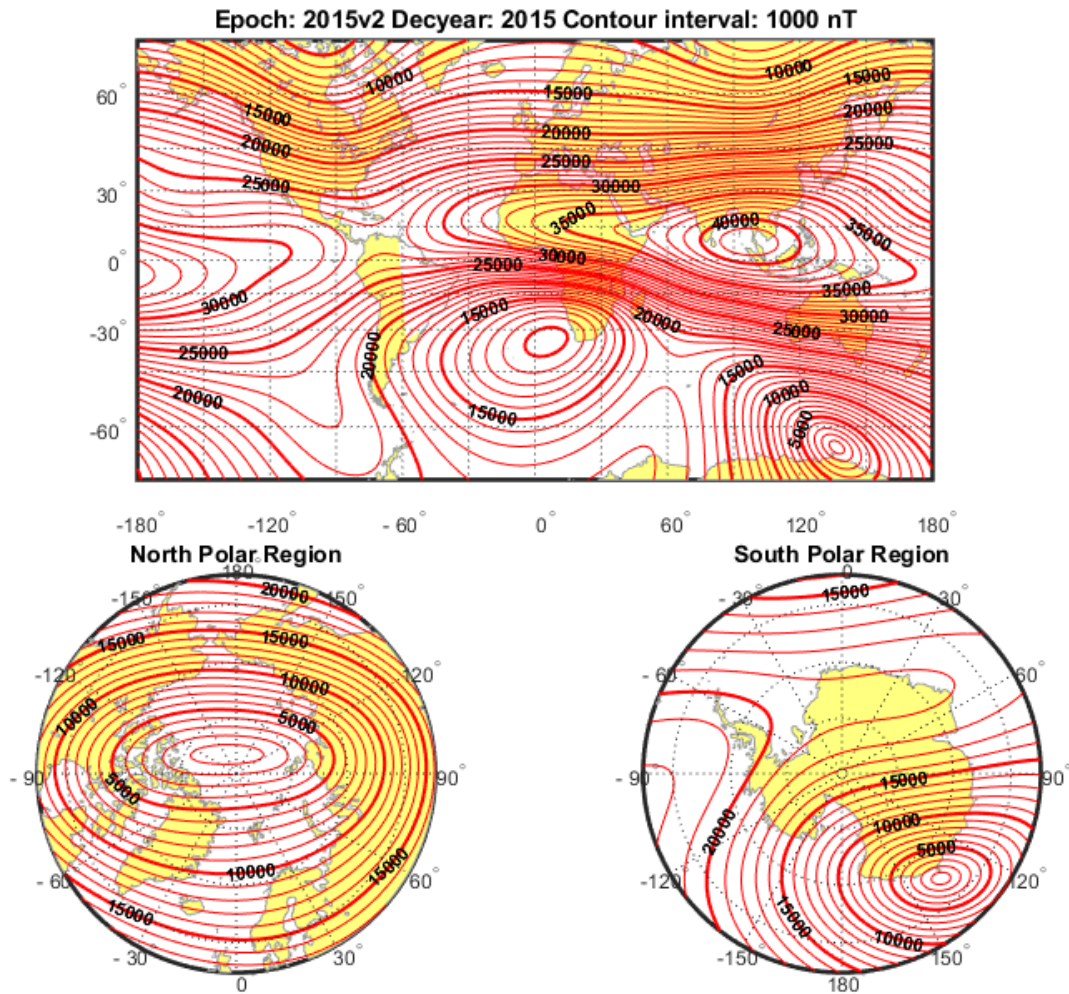



Figure 4: Horizontal Intensity, H (nT)

```

hDEC = figure;
set(hDEC, 'Position', [0 0 827 620], 'Color', 'white')
astPlotWMMContours( WMMResults, plotWMM, 5, landAreas, geod_lat, geod_lon, decimal_year, model_ep

```

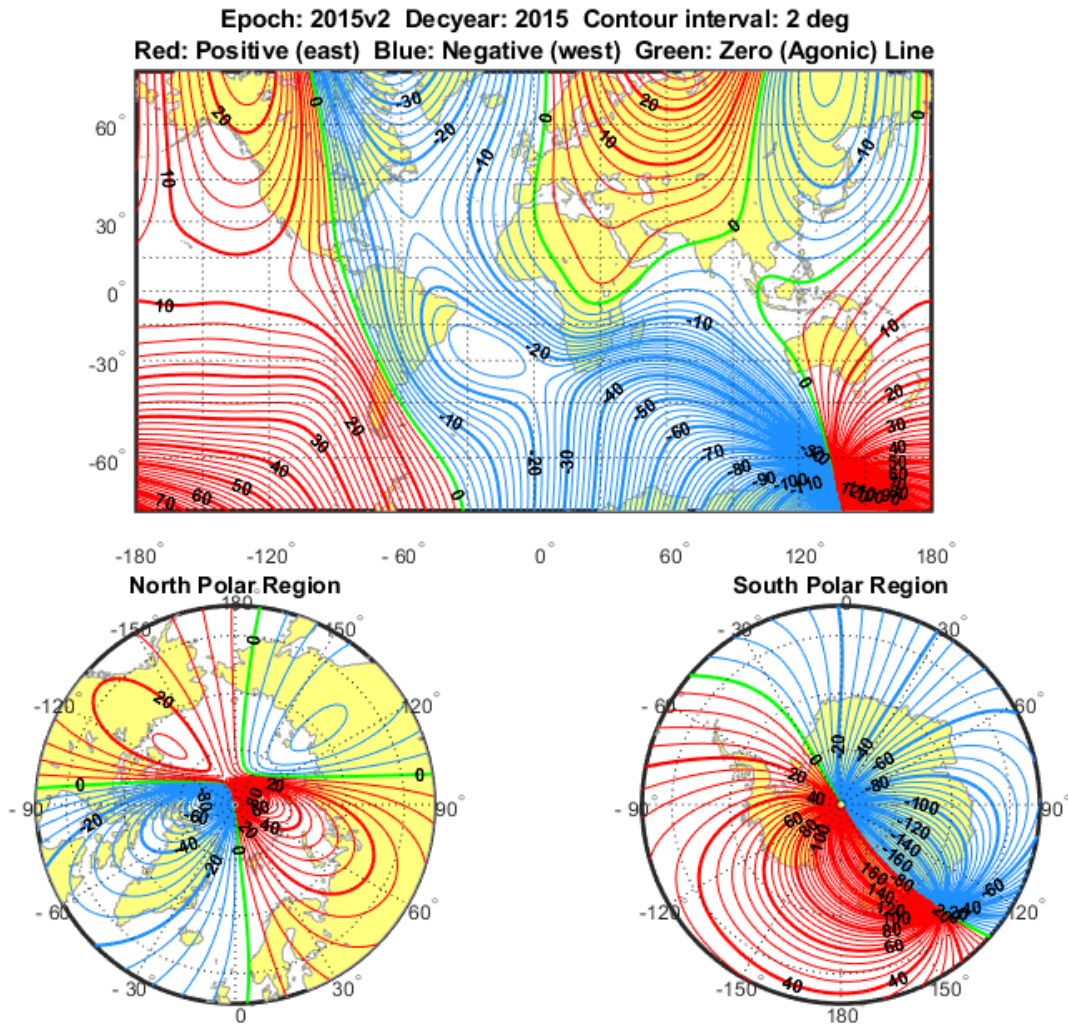


Figure 5: Declination, DEC (deg)

```

hDIP = figure;
set(hDIP,'Position',[0 0 827 620],'Color','white')
astPlotWMMContours( WMMResults, plotWMM, 6, landAreas, geod_lat, geod_lon, decimal_year, model_ep
    
```

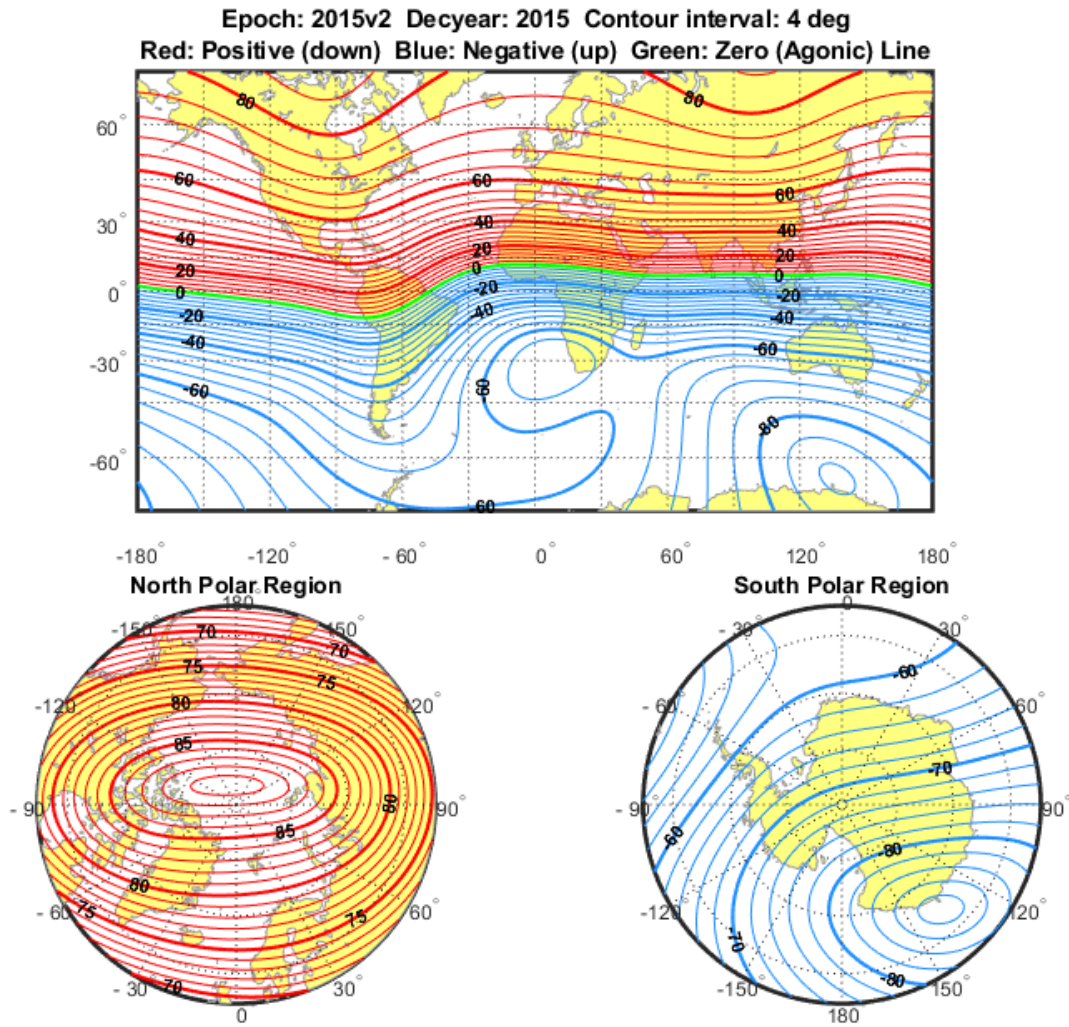


Figure 6: Inclination, DIP (deg)

```
hF = figure;
set(hF,'Position',[0 0 827 620],'Color','white')
astPlotWMMContours( WMMResults, plotWMM, 7, landAreas, geod_lat, geod_lon, decimal_year, model_ep
```

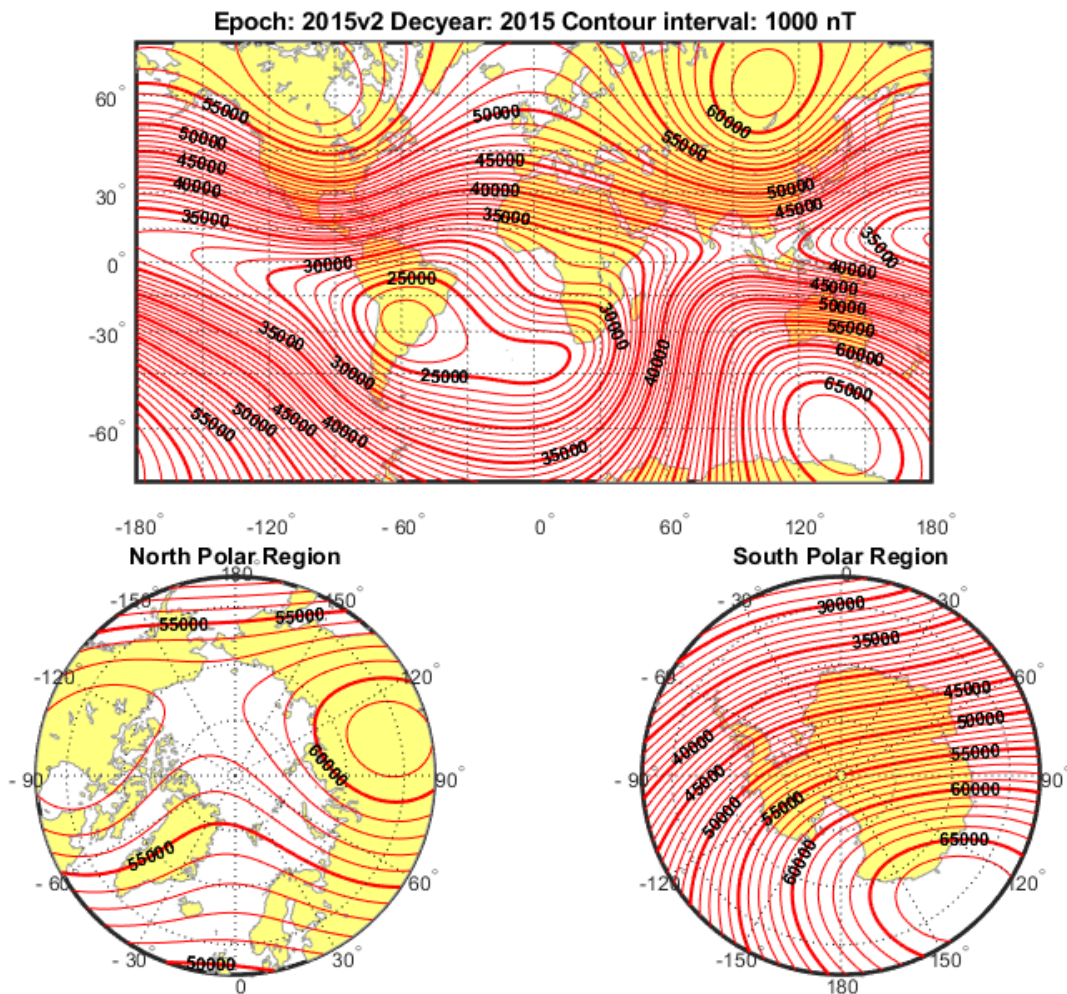



Figure 7: Total Intensity, F (nT)
 close (hX, hY, hZ, hH, hDEC, hDIP, hF)

Visualizing Geoid Height for Earth Geopotential Model 1996

This example shows how to calculate the Earth's Geoid height using the EGM96 Geopotential Model of the Aerospace Toolbox™ software. It also shows how to visualize the results with contour maps overlaid on maps of the Earth. The Mapping Toolbox™ and Simulink® 3D Animation™ are required to generate the visualizations.

Generating Values for Earth Geopotential Model 1996

Calculate values for the Earth's Geopotential using the `geoidheight` function to implement the EGM96 Geopotential Model.

The following code can be used to generate 260281 data points for calculating values of the Earth's Geoid height using `geoidheight`. To reduce computational overhead, this example includes a mat-file that contains this data.

```
% % Set amount of increment between degrees
% gridDegInc = 0.5; %degrees
%
% % Longitude value in degrees to use for latitude sweep.
% lon = -180:gridDegInc:180; %degrees
%
% % Geodetic Latitude values to sweep.
% geod_lat = -90:gridDegInc:90; %degrees
%
% % Loop through longitude values for each array of latitudes -90:90.
% for lonIdx = size(lon,2):-1:1
%
% % Longitude must be the same dimension as the latitude array
% lon = lon(lonIdx)*ones(1,numLatitude); % degrees
% geoidResults(1:end,lonIdx) = geoidheight(geod_lat,lon,'None');
%
% end
```

Loading Geoid Data File and Coastal Data

```
geoidFileName = 'GeoidResults_05deg_180.mat';
load(geoidFileName);
coast = load('coastlines.mat');
```

Plot 2-D View of Geoid Height

```
% Create 2-D plot using |meshm|
h2D = figure;
set(h2D,'Position',[20 75 700 600],'Toolbar','figure');

% Reference matrix for mapping geoid heights to lat/lon on globe.
RRR = makerefmat('RasterSize',size(geoidResults), ...
    'Latlim', [-90 90], 'Lonlim', [-180 180] );

ast2DGeoidPlot(RRR,geoidResults,coast,gridDegInc)

% Viewing Geoid height using VR canvas
www2D = vrworld('astGeoidHeights.wrl');
open(www2D)

% Actual geoid heights for reference
```

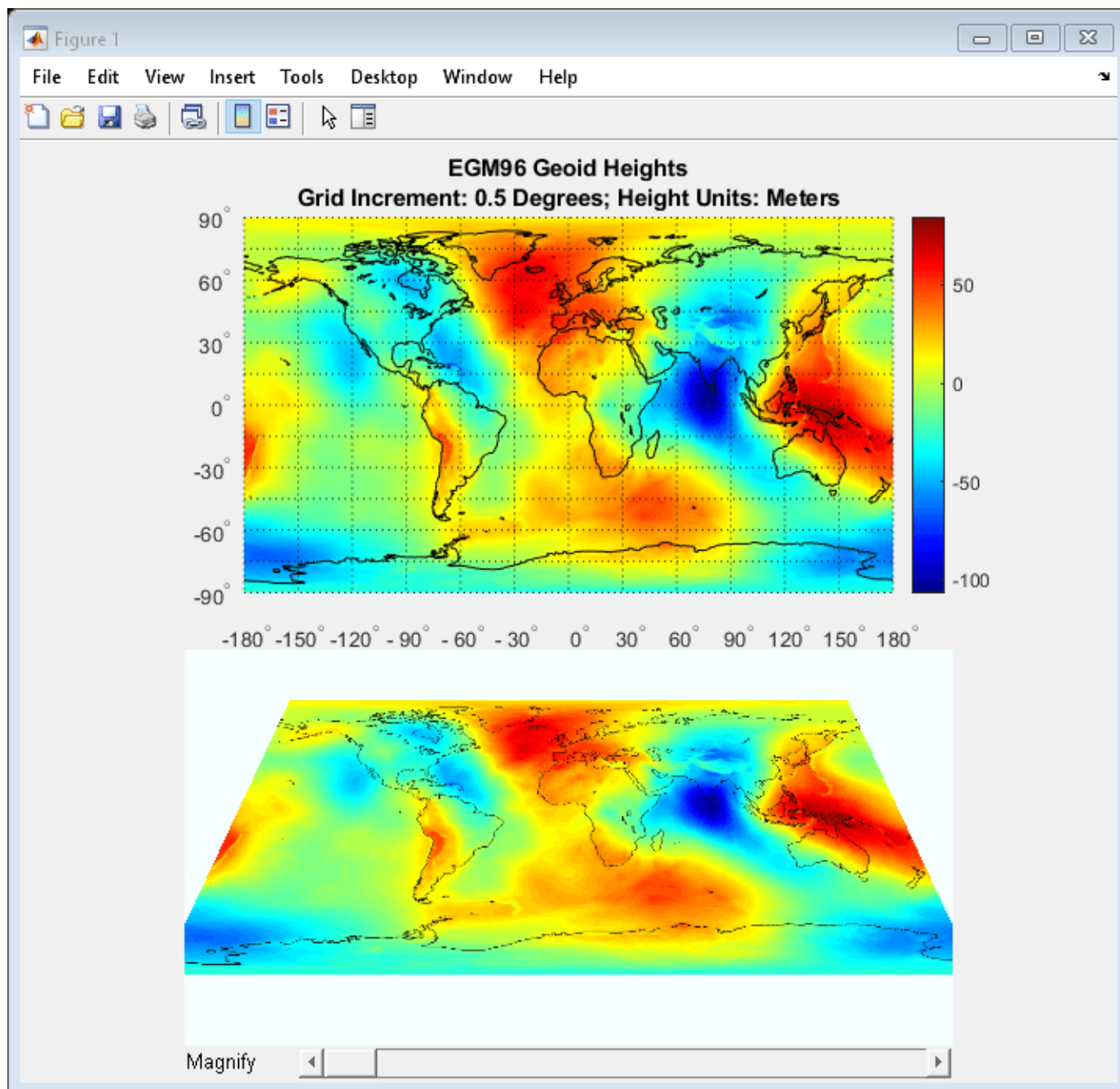


```
geoidGrid = vrnoded(www2D, 'EGM96_Grid');
actualHeights = getfield(geoidGrid, 'height'); %#ok<GFLD>

% Initialize heights to 0 for slider control
geoidGrid.height = 0*actualHeights;

% Size canvas for plotting and set parameters
geoidcanvas2D = vr.canvas(www2D, 'Parent', h2D, ...
    'Antialiasing', 'on', 'NavSpeed', 'veryslow', ...
    'NavMode', 'Examine', 'Units', 'normalized', ...
    'Viewpoint', 'Perspective', 'Position', [.15 .04 .7 .42]);

% Create slider
slid=astGeoidSlider(geoidcanvas2D);
```



Plot 3-D View of Geoid Height

```
h3D = figure;
set(h3D,'Position',[20 75 700 600]);

% Set up axes
hmapaxis = axesm('globe','Grid','on');
set(hmapaxis,'Position',[.1 .5 .8 .4])

view(85,0)
```

```
axis off

% Plot data on 3-D globe
meshm(geoidResults,RRR)

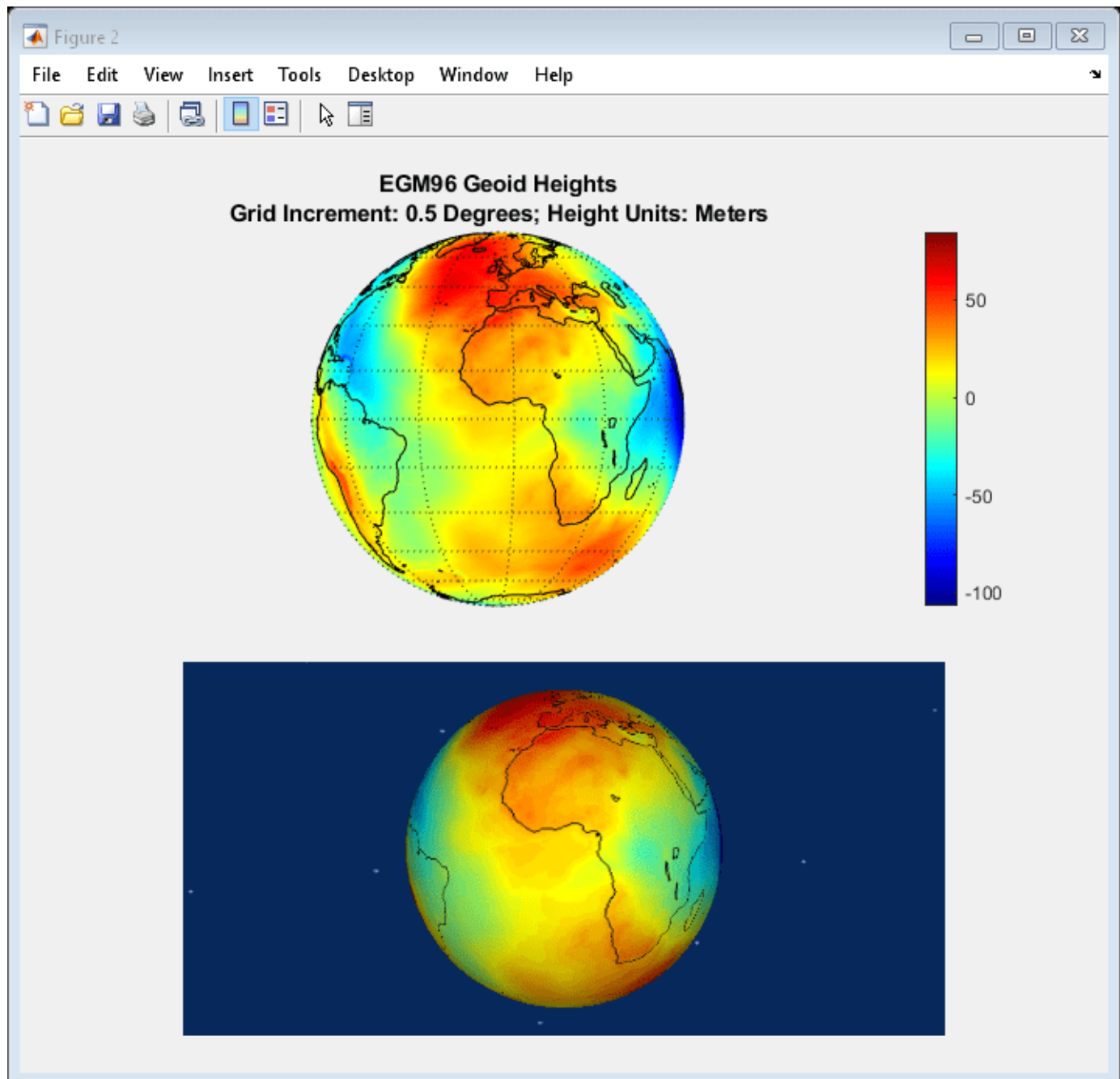
% Plot land mass outline
plotm(coast.coastlat,coast.coastlon,'Color','k')
colormap('jet');

% Plot Title
title({'EGM96 Geoid Heights';['Grid Increment: ',num2str(gridDegInc), ' Degrees; Height Units: ']});

colorbar;

% 3-D Globe: Geoid Height Using VR Canvas
www3D = vrworld('astGeoidSphere.wrl');
open(www3D)

% Position canvas
geoidcanvas3D = vr.canvas(www3D,'Parent',h3D,...
    'Antialiasing','on','NavSpeed','veryslow',...
    'NavMode','Examine','Units','normalized',...
    'Position',[.15 .04 .7 .4]);
vrdrawnow;
```

**Clean Up**

```
close(h2D,h3D)  
close(www2D);close(www3D);  
delete(www2D);delete(www3D);
```

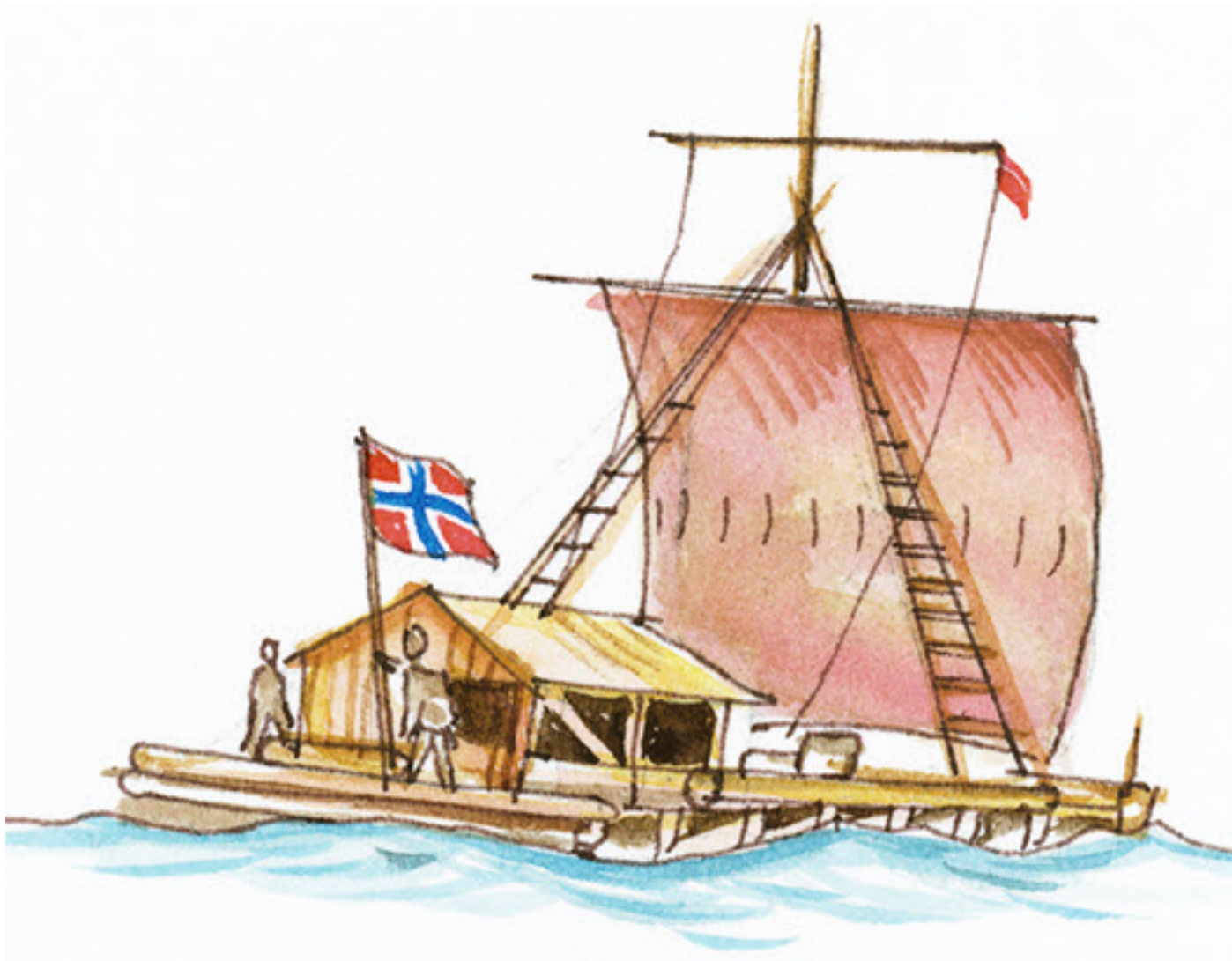

Marine Navigation Using Planetary Ephemerides

This example shows how to use the planetary ephemerides and a Earth Centered Inertial to Earth Centered Earth Fixed (ECI to ECEF) transformation to perform celestial navigation of a marine vessel.

This example uses the Mapping Toolbox™. You must also download data for the example using the `aeroDataPackage` command.



This example uses the route followed by the 1947 expedition across the Pacific Ocean Kon-Tiki. The expedition, led by Thor Heyerdahl, aimed to prove the theory that the Polynesian islands were populated by people from South America in pre-Columbian times. The expedition took 101 days and sailed from the port of Callao, Peru to the Raroia atoll, French Polynesia.



Notes: This example loosely recreates the expedition route. It takes some liberties to show the planetary ephemerides and ECI to ECEF transformation simply.

Load Vessel Track

Load the `astKonTikiData.mat` file. It contains the ship trajectory, velocity and course for this example. This file stores, the latitude and longitude for the different track points in the variables "lat" and "long", respectively. The variables contain enough data for one track point per day from the port of Callao to the Raroia atoll. Additionally, this file also stores values for each day's vessel velocity in knots per day "V" and course in deg "T".

```
load astKonTikiData
```

Create an Observation Structure

The nautical reduction process is a series of steps that a navigator follows to determine the latitude and longitude of his vessel. It is based on the theory described in *The American Practical Navigator*[1], the *Nautical Almanac*[2], and the *Explanatory Supplement to the Astronomical*

Almanac[3]. The process uses observational data obtained from a sextant, clock, compass, and navigational charts. It returns the intercept (p) and true azimuth (Z) for each of the observed objects. This example uses an observation structure array, `obs`, to contain the observational data. The fields for the structure array are:

- `h`: Height of eye level of the observer, in m.
- `IC`: Sextant's index correction, in deg.
- `P`: Local ambient pressure, in mb.
- `T`: Local temperature, in C.
- `year`: Local year at the time of the observation.
- `month`: Local month at the time of the observation.
- `day`: Local day at the time of the observation.
- `hour`: Local hour at the time of the observation.
- `UTC`: Coordinated Universal Time for the observation, represented as a six element vector with year, month, day, hour, minutes, and seconds.
- `Hs`: Sextant altitude of the celestial object above the horizon, in deg.
- `object`: Celestial object used for the measurement (i.e., Jupiter, Neptune, Saturn, etc).
- `latitude`: Estimated latitude of the vessel at the time of the observation, in deg.
- `longitude`: Estimated longitude of the vessel at the time of the observation, in deg.
- `declination`: Declination of the celestial object, in deg.
- `altitude`: Distance from the surface of the earth to the celestial object, in km.
- `GHA`: Greenwich Hour Angle, which is the angle in degrees of the celestial object relative to the Greenwich meridian.

For simplicity, assume that all measurements are taken at the same location in the boat, with the same sextant, at the same ambient temperature and pressure:

```
obs.h = 4;
obs.IC = 0;
obs.P = 982;
obs.T = 15;
```

The expedition departed on April 28th 1947. As a result, initialize the structure for the observation for this date:

```
obs.year = 1947;
obs.month = 4;
obs.day = 28;
```

Initialize Dead Reckoning Process for Navigation

To start the dead reckoning process, define the initial conditions for the position of the vessel. Store the latitude for a fixed solution for the latitude and longitude in the `latFix` and `longFix` variables, respectively. In this example, for the first fix location, use the latitude and longitude of Callao, Peru:

```
longFix = zeros(size(long));
latFix = zeros(size(lat));
longFix(1) = long(1);
latFix(1) = lat(1);
```


Daily Dead Reckoning

For this example, assume that a fix is obtained daily using the observational data. Therefore, this example uses a "for loop" for each observation. The variable "m" acts as a counter representing every elapsed day since the departure from the port:

```
for m = 1:size(lat,1)-1
```

Increment the day and make day adjustments for the months of June and April, both of which have only 30 days:

```
    obs.day = obs.day + 1;  
    [obs.month,obs.day] = astHelperDayCheck(obs.year,obs.month,obs.day);
```

Actual Latitude and Longitude

Extract the vessel actual position for each day from the track points loaded earlier. The example uses this value to calculate the local time zone and the position of the selected planets in the sky:

```
    longActual = long(m+1);  
    latActual = lat(m+1);
```

Planet Selection

Select the planets for observation if they are visible to the vessel for the given latitude and longitude. The following code uses precalculated data:

```
    if longActual>-90  
        obs.object = {'Saturn';'Neptune'};  
    elseif longActual<=-90 && longActual>-95  
        obs.object = {'Saturn';'Neptune';'Jupiter'};  
    elseif longActual<=-95  
        obs.object = {'Neptune';'Jupiter'};  
    end
```

UTC Time Calculation

Adjust local time to UTC depending on the assumed longitude. For this example, assume that all observations are taken at the same time every day at 8 p.m. local time.

```
    obs.hour = 20;
```

For the dead reckoning process, update the observation structure with the estimate of the current location. In this case, the location is estimated using the previous fix, the vessel's velocity V, and course T.

```
    obs.longitude = longFix(m)+(1/60)*V(m)*sind(T(m))/cosd(latFix(m));  
    obs.latitude = latFix(m)+(1/60)*V(m)*cosd(T(m));
```

Adjust the local time to UTC using the helper function `astHelperLongitudeHour`. This function adjusts the UTC observation time depending on the estimated longitude of the vessel.

```
    obs.UTC = astHelperLongitudeHour(obs);
```

Sextant Altitude Calculation

For each of the planets, the `astHelperNauticalCalculation` helper function calculates the sextant measurement that the crew in the Kon-Tiki would have measured. This function models the actual

behavior of the planets, while compensating for the local conditions. This function uses the planetary ephemeris and the ECI to ECEF transformation matrix. The analysis doesn't include planetary aberration, gravitational light deflection, and aberration of light phenomena.

```
obs.Hs = astHelperNauticalCalculation(obs,latActual,longActual);
```

Calculate position

The following calculations replace the use of the nautical almanac. They include the use of the planetary ephemerides and the ECI to ECEF transformation matrix.

Initialize declination, Greenwich Hour Angle (GHA), and altitude for the observed object:

```
obs.declination = zeros(size(obs.Hs));
obs.GHA = zeros(size(obs.Hs));
obs.altitude = zeros(size(obs.Hs));
```

Calculate the modified Julian date for the measurement time:

```
mjd = mjuliandate(obs.UTC);
```

Calculate the difference between UT1 and UTC:

```
dUT1 = deltaUT1(mjd, 'Action', 'None');
```

Calculate the ECI to ECEF transformation matrix using the values of TAI-UTC (dAT) from the U.S. Naval Observatory:

```
dAT = 1.4228180;
TM = dcmeci2ecef('IAU-76/FK5', obs.UTC, dAT, dUT1);
```

Calculate Julian date for Terrestrial Time to approximate the Barycentric Dynamical Time:

```
jdTT = juliandate(obs.UTC)+(dAT+32.184)/86400;
```

Calculate declination, Greenwich Hour Angle, and altitude for each of the celestial objects:

```
for k =1:length(obs.object)
```

Calculate the ECI position for every planet:

```
posECI = planetEphemeris(jdTT, 'Earth', obs.object{k}, '405', 'km');
```

Calculate the ECEF position of every planet:

```
posECEF = TM*posECI';
```

Calculate the Greenwich Hour Angle (GHA) and declination using the ECEF position:

```
obs.GHA(k) = -atan2d(posECEF(2),posECEF(1));
obs.declination(k) = atan2d(posECEF(3),sqrt(posECEF(1)^2 + ...
    posECEF(2)^2));
```

Calculate the distance from the surface of the Earth to the center of the planet using the ECEF to LLA transformation function:

```
posLLA = ecef2lla(1000*posECEF');
obs.altitude(k) = posLLA(3);
```

end

Sight Reduction for Planetary Objects

Reduce sight for each of the planets specified in the observation structure array:

```
[p,Z] = astHelperNauticalReduction(obs);
```

Calculate the increments to the latitude and longitude from the last fix for the current fix using the following equations. These equations are based on the Nautical Almanac.

```
Ap = sum(cosd(Z).^2);  
Bp = sum(cosd(Z).*sind(Z));  
Cp = sum(sind(Z).^2);  
Dp = sum(p.*cosd(Z));  
Ep = sum(p.*sind(Z));  
Gp = Ap*Cp-Bp^2;
```

Calculate the increments for latitude and longitude according to the reduction:

```
deltaLongFix = (Ap*Ep-Bp*Dp)/(Gp*cosd(latFix(m)));  
deltaLatFix = (Cp*Dp-Bp*Ep)/Gp;
```

After the increments for the latitude and longitude are calculated, add them to the estimated location, obtaining the fix for the time of observation:

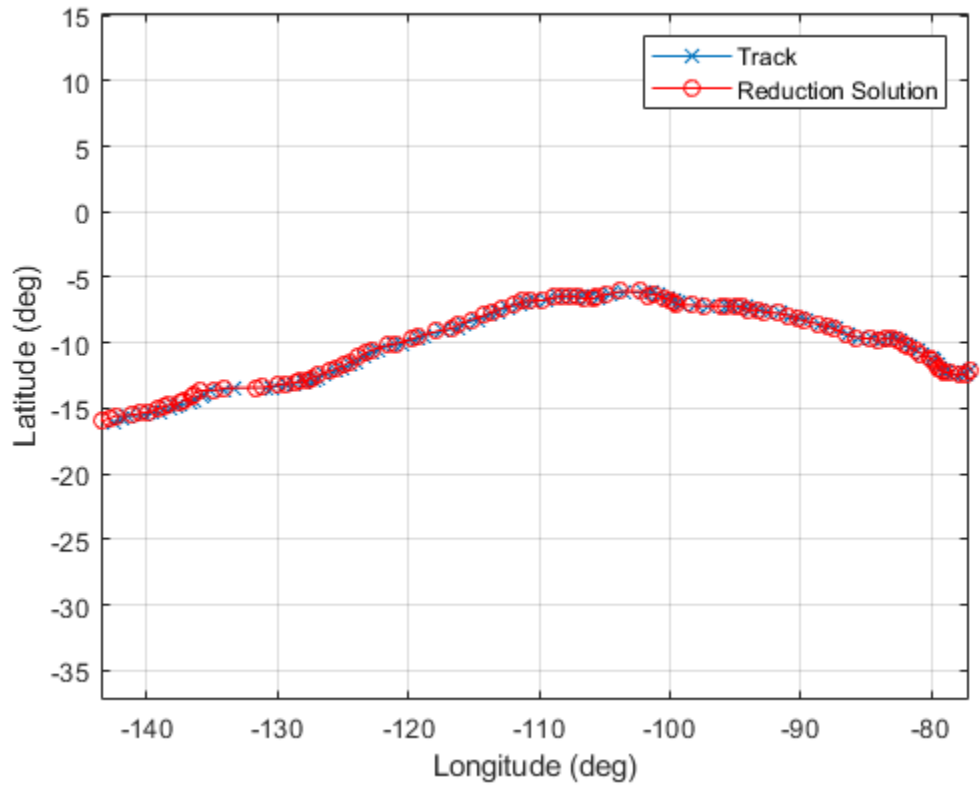
```
longFix(m+1) = obs.longitude + deltaLongFix;  
latFix(m+1) = obs.latitude + deltaLatFix;
```

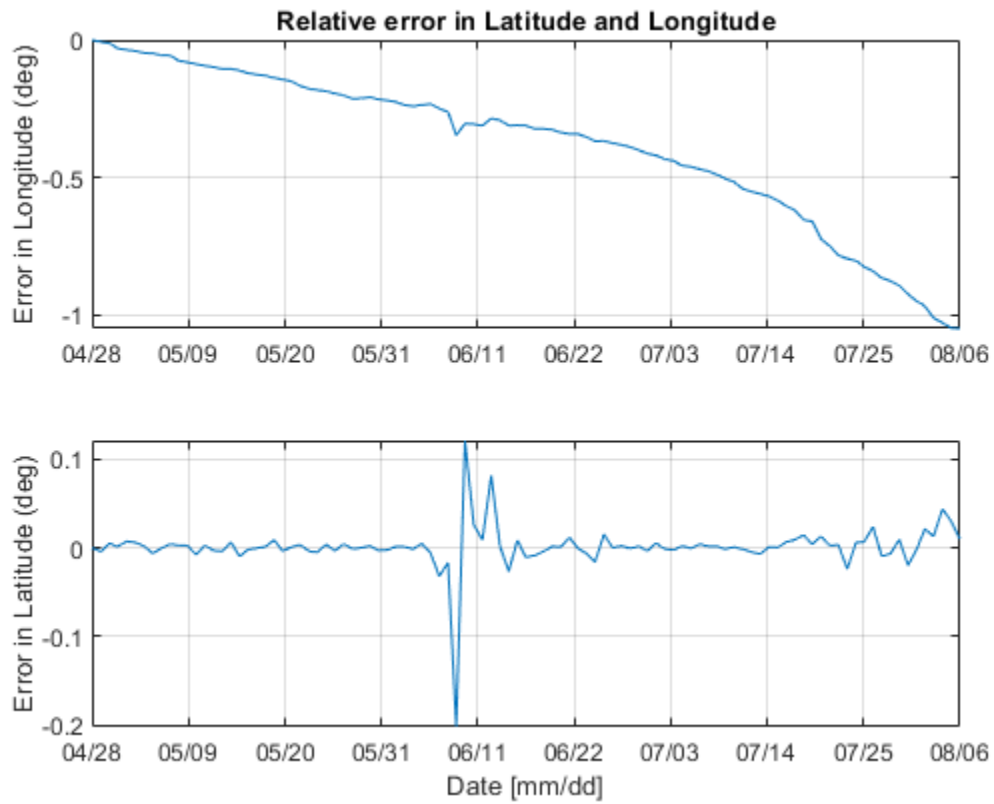
end

Navigation Solution Visualization

The following figure shows the actual track and sight reduction solutions:

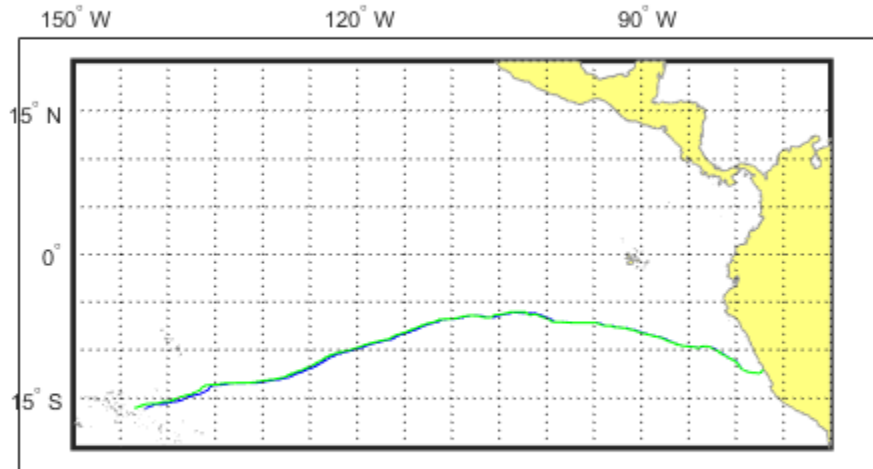
```
astHelperVisualization(long,lat,longFix,latFix,'Plot')
```





You can use the Mapping Toolbox to obtain a more detailed graph depicting the sight reduction solutions with the American continent and French Polynesia.

```
astHelperVisualization(long,lat,longFix,latFix,'Map')
```



The relative error in longitude and latitude is accumulated as the vessel sails from Callao to Raroia. This error is due to small errors in the measurement of the sextant altitude. For June 9th, the reduction method calculates a true azimuth (Z) for Neptune and Jupiter. The true azimuths for Neptune and Jupiter are close to 180 deg apart. This difference causes a small peak in the relative error. This error, however, is still within the reduction method error boundaries.

References

- [1] Bowditch, N. The American Practical Navigator. National Geospatial Intelligence Agency, 2012.
- [2] United Kingdom Hydrographic Office. Nautical Almanac 2012 Commercial Edition. Paradise Publications, Inc. 2011.
- [3] Urban, Sean E. and P. Kenneth Seidelmann. Explanatory Supplement to the Astronomical Almanac. 3rd Ed., University Science Books, 2013.
- [4] United States Naval Observatory.

Estimate Sun Analemma Using Planetary Ephemerides and ECI to AER Transformation

This example shows how to estimate the analemma of the Sun. The analemma is the curve that represents the variation of the angular offset of the Sun from its mean position on the celestial sphere relative to a specific geolocation on the Earth surface. In this example, the analemma is estimated relative to the Royal Observatory at Greenwich, United Kingdom. After the estimation, the example plots the analemma.

This example uses data that you can download using the `aeroDataPackage` command.

Identify the Dates of a Year over Which to Calculate the Analemma of the Sun

Specify the dates for which to calculate the analemma. In this example, these dates range for the year 2014 from January 1st to December 31st at noon UTC.

```
dv = datetime(2014,1,1:365,12,0,0);
dvUTC = [dv.Year' dv.Month' dv.Day' dv.Hour' dv.Minute' dv.Second'];
```

Calculate the Position of the Sun

Use the `planetEphemeris` function to calculate the position of the Sun. In this example:

- The `tdbjuliandate` function calculates the Julian date for the dynamic barycentric time (TDB).
- The `tdbjuliandate` function requires the terrestrial time (TT).

The calculation of the terrestrial time in seconds from UTC requires the difference in Coordinated Universal Time (UTC) and International Atomic Time (TAI).

- For 2014, this difference (dAT) is 35 seconds.
- The approximate terrestrial time (secTT) is the dAT + 32.184 seconds.
- The terrestrial time in year, month, day, hour, minutes, and seconds is contained in the dvTT array.

```
dAT = 35;
secTT = dAT + 32.184;
dvTT = dv + secTT/86400;
```

Estimate the Julian date for the dynamic barycentric time based on the terrestrial time using the array dvTT:

```
jdTDB = tdbjuliandate([dvTT.Year' dvTT.Month' dvTT.Day' dvTT.Hour' dvTT.Minute' dvTT.Second']);
```

Determine the position of the Sun for these dates:

```
posSun = planetEphemeris(jdTDB, 'Earth', 'Sun')*1000;
```

Calculate Difference Between UTC and Principal Universal Time (UT1)

Calculate the difference between UTC and UT1, `deltaUT1`, using the modified Julian dates for UTC.

```
mjdUTC = mjuliandate(dvUTC);
dUT1 = deltaUT1(mjdUTC);
```

Calculate Polar Motion and Displacement of the Celestial Intermediate Pole (CIP)

Calculate the polar motion and displacement of the CIP using the modified Julian dates for UTC.

```
PM = polarMotion(mjdUTC);
dCIP = deltaCIP(mjdUTC);
```

Specify the Geopotential Position of the Royal Observatory at Greenwich, United Kingdom

Specify the geopotential location for the position against which to estimate the analemma. In this example, this location is the latitude, longitude, and altitude for the Royal Observatory at Greenwich (51.48 degrees North, 0.0015 degrees West, 0 meters altitude).

```
LLAGreenwich = [51.48, -0.0015, 0];
aer = eci2aer(posSun, dvUTC, repmat(LLAGreenwich, length(jdTDB), 1), ...
    'deltaAT', dAT*ones(length(jdTDB), 1), 'deltaUT1', dUT1, ...
    'PolarMotion', PM, 'dCIP', dCIP);
```

Specify Days Within the Year of the Analemma That You Want to Plot

On the analemma, you can plot days of interest within the year of the analemma. This example plots:

- The first day of each month in 2014.
- The summer and winter solstices.
- The spring and fall equinoxes.

To get the first day of each month in 2014:

```
aerFirstMonth = aer(dvUTC(:,3)==1, :);
```

To get solstices and equinoxes (for 2014 are 3/20, 6/21, 9/22, 12/21):

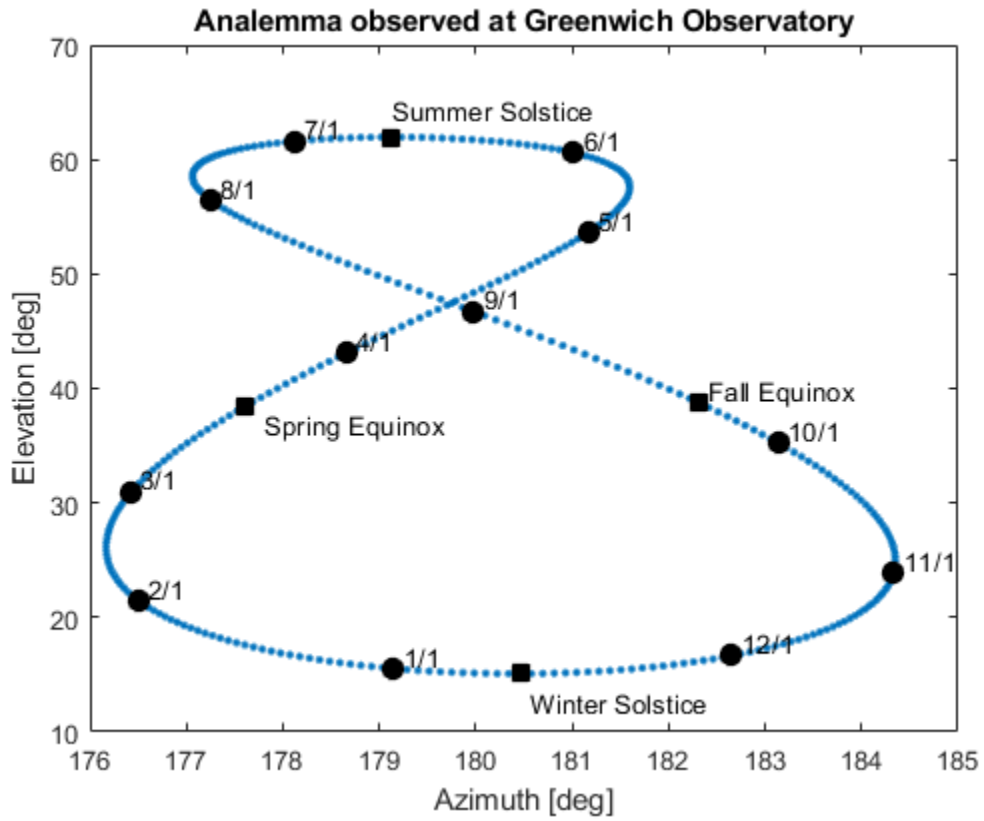
```
solsticeEquinox = [ aer(and(dvUTC(:,2)==3, dvUTC(:,3)==20), 1) aer(and(dvUTC(:,2)==3, dvUTC(:,3)==20), 1)
    aer(and(dvUTC(:,2)==6, dvUTC(:,3)==21), 1) aer(and(dvUTC(:,2)==6, dvUTC(:,3)==21), 1)
    aer(and(dvUTC(:,2)==9, dvUTC(:,3)==22), 1) aer(and(dvUTC(:,2)==9, dvUTC(:,3)==22), 1)
    aer(and(dvUTC(:,2)==12, dvUTC(:,3)==21), 1) aer(and(dvUTC(:,2)==12, dvUTC(:,3)==21), 1)
```

Plot Results

Plot the analemma. Along the analemma, plot points for the whole year, first days of the month, equinoxes, and solstices.

```
for ii = 12:-1:1
    firstDays{ii} = [num2str(ii) '/' num2str(1)];
end

f = figure;
plot(aer(:,1), aer(:,2), '.', ...
    solsticeEquinox(:,1), solsticeEquinox(:,2), 'ks', ...
    aerFirstMonth(:,1), aerFirstMonth(:,2), 'ko', ...
    'MarkerSize', 8, 'MarkerFaceColor', 'k');
title('Analemma observed at Greenwich Observatory');
xlabel('Azimuth [deg]');
ylabel('Elevation [deg]');
axis([176, 185, 10, 70])
text(aerFirstMonth(:,1)+.1, aerFirstMonth(:,2)+1.2, firstDays, 'Color', 'k', 'HorizontalAlignment', 'left');
text(solsticeEquinox(1,1)+.2, solsticeEquinox(1,2)-1.5, 'Spring Equinox', 'Color', 'k', 'HorizontalAlignment', 'left');
text(solsticeEquinox(2,1), solsticeEquinox(2,2)+2.5, 'Summer Solstice', 'Color', 'k', 'HorizontalAlignment', 'left');
text(solsticeEquinox(3,1)+.1, solsticeEquinox(3,2)+1.2, 'Fall Equinox', 'Color', 'k', 'HorizontalAlignment', 'left');
text(solsticeEquinox(4,1)+.1, solsticeEquinox(4,2)-2.5, 'Winter Solstice', 'Color', 'k', 'HorizontalAlignment', 'left');
```



Display Flight Trajectory Data Using Flight Instruments and Flight Animation

This example shows how to visualize flight trajectories in a UI figure window using flight instrument components. In this example, you will create and configure standard flight instruments in conjunction with the `Aero.Animation` object.

Load Recorded Data for Flight Trajectories and Instrument Display

Load logged aircraft position, attitude, and time to the workspace.

```
load simdata
```

Create Animation Interface

To display the flight trajectories stored in the flight trajectory data, create an `Aero.Animation` object. The aircraft used in this example is the Piper PA24-250 Comanche.

```
h = Aero.Animation;  
h.createBody('pa24-250_orange.ac', 'Ac3d');  
h.Bodies{1}.TimeSeriesSource = simdata;  
h.Camera.PositionFcn = @staticCameraPosition;  
h.Figure.Position(1) = h.Figure.Position(1) + 572/2;  
h.show();
```



Create Flight Instruments

Create a UI figure window to contain the flight instruments.

```
fig = uifigure('Name','Flight Instruments',...
    'Position',[h.Figure.Position(1)-572 h.Figure.Position(2)+h.Figure.Position(4)-502 572 502],
    'Color',[0.2667 0.2706 0.2784],'Resize','off');
```

Load panel image into an axis:

```
imgPanel = imread('astFlightInstrumentPanel.png');
ax = uiaxes('Parent',fig,'Visible','off','Position',[10 30 530 460],...
    'BackgroundColor',[0.2667 0.2706 0.2784]);
image(ax,imgPanel);
disableDefaultInteractivity(ax);
```

Create standard flight instruments for navigation:

Create altimeter:

```
alt = uiaeroaltimeter('Parent',fig,'Position',[369 299 144 144]);
```

Create heading indicator:

```
head = uiaeroheading('Parent',fig,'Position',[212 104 144 144]);
```

Create airspeed indicator:

```
air = uiaeroairspeed('Parent',fig,'Position',[56 299 144 144]);
```

Change the airspeed indicator limits according to the Piper PA 24-250 Comanche capabilities:

```
air.Limits = [20 200];
air.ScaleColorLimits = [0 50;40 160;160 190;190 200];
```

Create artificial horizon:

```
hor = uiaerohorizon('Parent',fig,'Position',[212 299 144 144]);
```

Create climb rate indicator:

```
climb = uiaeroclimb('Parent',fig,'Position',[369 104 144 144]);
```

Change the climb indicator maximum climb rate according to the aircraft capabilities:

```
climb.MaximumRate = 4000;
```

Create turn coordinator:

```
turn = uiaeroturn('Parent',fig,'Position',[56 104 144 144]);
```

To update the flight instruments and animation figure, assign the `ValueChangingFcn` callback to the `astHelperFlightInstrumentsAnimation` helper function. Then, when a time is selected on the slider, the flight instruments and animation figure will be updated according to the selected time value.

```
sl = uislider('Parent',fig,'Limits',[simdata(1,1) simdata(end,1)],'FontColor','white');
sl.Position = [50 60 450 3];
sl.ValueChangingFcn = @(sl,event) astHelperFlightInstrumentsAnimation(fig,simdata,h,event);
```

To display the time selected in the slider, create a label component.

```
lbl = uilabel('Parent',fig,'Text',['Time: ' num2str(sl.Value,4) ' sec'],'FontColor','white');
lbl.Position = [230 10 90 30];
```

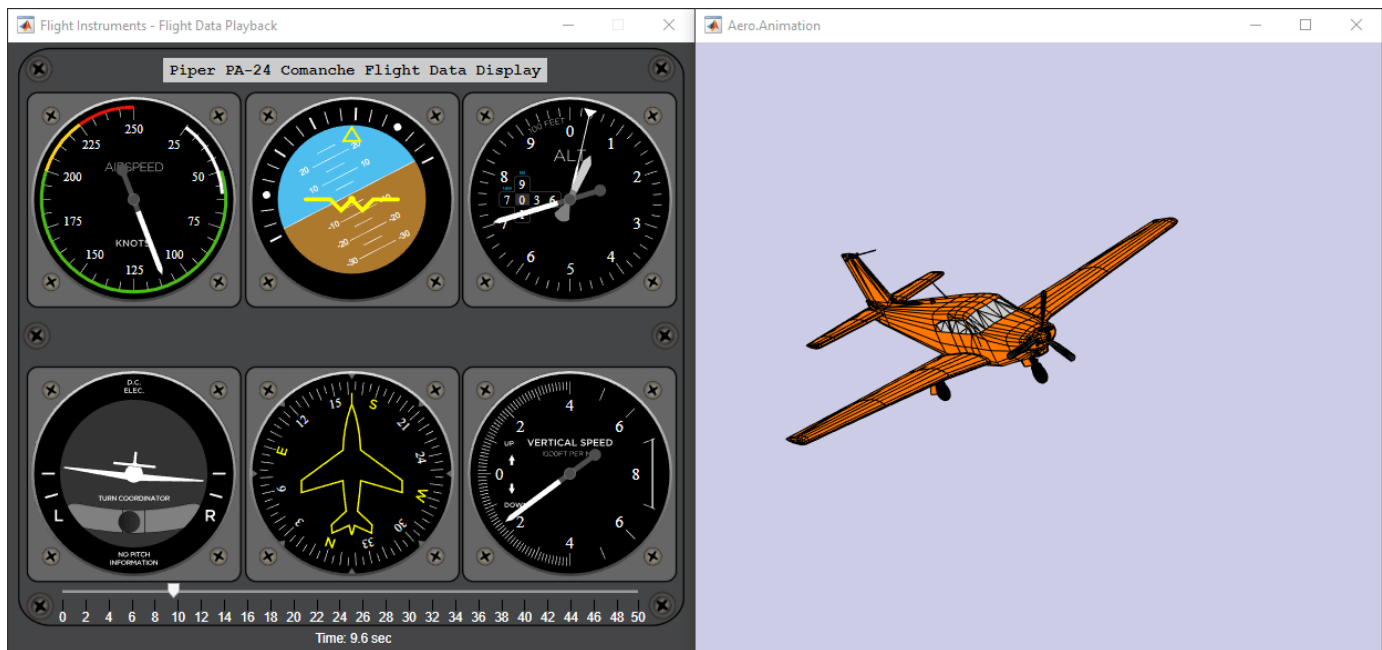


Aerospace Flight Instruments in App Designer

This app shows how to display flight status information with standard cockpit instrumentation using Aerospace Toolbox flight instruments in App Designer. On startup, the app loads saved flight data from a MAT-file and starts a new `Aero.Animation` figure window. The app uses six flight instruments to display flight data corresponding with the time selected in the slider. The animation window updates to reflect the aircraft orientation at the selected time.

This example demonstrates the following app building tasks:

- Use a `StartupFcn` callback to load data from a file and create an `Aero.Animation` object.
- Use aerospace flight instrument components to visualize flight status information: Airspeed Indicator, Artificial Horizon, Altimeter, Turn Coordinator, Heading Indicator, and Climb Indicator
- Use the slider component `ValueChangedFcn` callback to set aerospace flight instrument component properties and interact with an `Aero.Animation` object.



Perform Controls and Static Stability Analysis with Linearized Fixed-Wing Aircraft

This example shows how to convert a fixed-wing aircraft to a linear time invariant (LTI) state-space model for linear analysis.

This example describes:

- Importing and filling data from a DATCOM file.
- Constructing a fixed-wing aircraft from DATCOM data.
- Calculating static stability of the fixed-wing aircraft.
- Linearizing the fixed-wing aircraft around an initial state.
- Validating the static stability analysis with a dynamic response.
- Isolating the elevator-to-pitch transfer function and designing a feedback controller for the elevator.

Defining the Fixed-Wing Aircraft and State

This example uses a DATCOM file created for the Sky Hogg aircraft.

First, import the DATCOM output file using `datcomimport`.

```
allData = datcomimport('astSkyHoggDatcom.out', false, 0);
skyHoggData = allData{1}

skyHoggData = struct with fields:
    case: 'SKYHOGG BODY-WING-HORIZONTAL TAIL-VERTICAL TAIL CONFIG'
    mach: [0.1000 0.2000 0.3000 0.3500]
    alt: [1000 3000 5000 7000 9000 11000 13000 15000]
    alpha: [-16 -12 -8 -4 -2 0 2 4 8 12]
    nmach: 4
    nalt: 8
    nalpha: 10
    rnnub: []
    hypers: 0
    loop: 2
    sref: 225.8000
    cbar: 5.7500
    blref: 41.1500
    dim: 'ft'
    deriv: 'deg'
    stmach: 0.6000
    tsmach: 1.4000
    save: 0
    stype: []
    trim: 0
    damp: 1
    build: 1
    part: 0
    highsymb: 1
    highasy: 0
    highcon: 0
    tjet: 0
    hypeff: 0
```

```
    lb: 0
    pwr: 0
    grnd: 0
    wsspn: 18.7000
    hsspn: 5.7000
    ndelta: 5
    delta: [-20 -10 0 10 20]
    deltal: []
    deltar: []
    ngh: 0
    grndht: []
    config: [1x1 struct]
    version: 1976
    cd: [10x4x8 double]
    cl: [10x4x8 double]
    cm: [10x4x8 double]
    cn: [10x4x8 double]
    ca: [10x4x8 double]
    xcp: [10x4x8 double]
    cma: [10x4x8 double]
    cyb: [10x4x8 double]
    cnb: [10x4x8 double]
    clb: [10x4x8 double]
    cla: [10x4x8 double]
    qqinf: [10x4x8 double]
    eps: [10x4x8 double]
    depsdalp: [10x4x8 double]
    clq: [10x4x8 double]
    cmq: [10x4x8 double]
    clad: [10x4x8 double]
    cmad: [10x4x8 double]
    clp: [10x4x8 double]
    cyp: [10x4x8 double]
    cnp: [10x4x8 double]
    cnr: [10x4x8 double]
    clr: [10x4x8 double]
    dcl_sym: [5x4x8 double]
    dcm_sym: [5x4x8 double]
    dclmax_sym: [5x4x8 double]
    dcdmin_sym: [5x4x8 double]
    clad_sym: [5x4x8 double]
    cha_sym: [5x4x8 double]
    chd_sym: [5x4x8 double]
    dcdi_sym: [10x5x4x8 double]
```

Next, prepare the DATCOM lookup tables.

DATCOM lookup tables might have missing values due to the tables only filling one value for the whole column.

This missing data is represented in the lookup tables as the value 99999 and can be filled using the "previous" method of fillmissing.

In this example, $C_{y\beta}$, $C_{n\beta}$, C_{Lq} , and C_{mq} have missing data.

```
skyHoggData.cyb = fillmissing(skyHoggData.cyb, "previous", "MissingLocations", skyHoggData.cyb == 99999);
skyHoggData.cnb = fillmissing(skyHoggData.cnb, "previous", "MissingLocations", skyHoggData.cnb == 99999);
```

```
skyHoggData.clq = fillmissing(skyHoggData.clq, "previous", "MissingLocations", skyHoggData.clq ==
skyHoggData.cmq = fillmissing(skyHoggData.cmq, "previous", "MissingLocations", skyHoggData.cmq ==
```

With the missing data filled, the fixed-wing aircraft can be constructed.

First, the fixed-wing aircraft is prepared with the desired aircraft name.

Optionally, the aircraft name can be extracted from the "case" field on the DATCOM struct by passing an empty fixed-wing object.

```
skyHogg = Aero.FixedWing();
skyHogg.Properties.Name = "Sky_Hogg";
skyHogg.DegreesOfFreedom = "3DOF";
[skyHogg, cruiseState] = datcomToFixedWing(skyHogg, skyHoggData);
```

The `datcomToFixedWing` will convert all compatible data from the `datcom` struct into the fixed-wing object and its state. However, the returned state still needs processing to get the desired initial conditions of the aircraft.

In this example, the environment, mass, inertia, airspeed, and center of pressure need adjusting.

```
h = 2000;
[T, a, p, rho] = atmoscoesa(convlength(h, "ft", "m"));
cruiseState.AltitudeMSL = h;
cruiseState.Environment.Temperature = convtemp(T, "K", "R");
cruiseState.Environment.SpeedOfSound = convvel(a, "m/s", "ft/s");
cruiseState.Environment.Pressure = convpres(p, "pa", "psf");
cruiseState.Environment.Density = convdensity(rho, "kg/m^3", "slug/ft^3");

cruiseState.U = 169.42;
cruiseState.Mass = 1299.214;
cruiseState.Inertia.Variables = [5787.969 0 117.64; 0 6928.93 0; -117.64 0 11578.329];
cruiseState.CenterOfPressure = [0.183, 0, 0];
```

Calculating Static Stability

Performing a static stability analysis helps determine the dynamic stability of the system without calculating a dynamic system response.

```
stability = staticStability(skyHogg, cruiseState)
```

stability=6x8 table

	U	V	W	Alpha	Beta	P	Q
FX	"Stable"	" "	" "	" "	" "	" "	" "
FY	" "	"Neutral"	" "	" "	" "	" "	" "
FZ	" "	" "	"Stable"	" "	" "	" "	" "
L	" "	" "	" "	" "	"Neutral"	"Neutral"	" "
M	"Stable"	" "	" "	"Stable"	" "	" "	"Stable"
N	" "	" "	" "	" "	"Neutral"	" "	" "

With statically stable forces and moments, with perturbations to forward and vertical speeds, and perturbations to angle of attack, the dynamic stability of the system tends towards an oscillating steady-state when perturbing the forward and vertical speeds.

To verify this behavior, use the Control System Toolbox™.

Linearizing the Fixed-Wing Aircraft

To use the tools within the Control System Toolbox™, linearize the aircraft around a state.

This is done by using the `linearize` method with the same cruise state as before.

```
linSys = linearize(skyHogg, cruiseState)
```

```
linSys =
```

```
A =
      XN      XD      U      W      Q
      XN      0      0      1      0      0
      XD      0      0      0      1      0
      U      0      1.319e-06 -0.001714 -0.0007608 0
      W      0      0      -0.002705 -0.3319      2.557
      Q      0      0      0.02379 -2.495      -26.41
      Theta 0      0      0      0      0      1
```

```
      Theta
      XN -2.586e-07
      XD -2.957
      U -0.5617
      W -4.867e-08
      Q 0
      Theta 0
```

```
B =
      Delta
      XN 0
      XD 0
      U -0.0004314
      W -0.02084
      Q -2.321
      Theta 0
```

```
C =
      XN      XD      U      W      Q      Theta
      XN      1      0      0      0      0      0
      XD      0      1      0      0      0      0
      U      0      0      1      0      0      0
      W      0      0      0      1      0      0
      Q      0      0      0      0      1      0
      Theta 0      0      0      0      0      1
```

```
D =
      Delta
      XN 0
      XD 0
      U 0
      W 0
      Q 0
      Theta 0
```

Continuous-time state-space model.

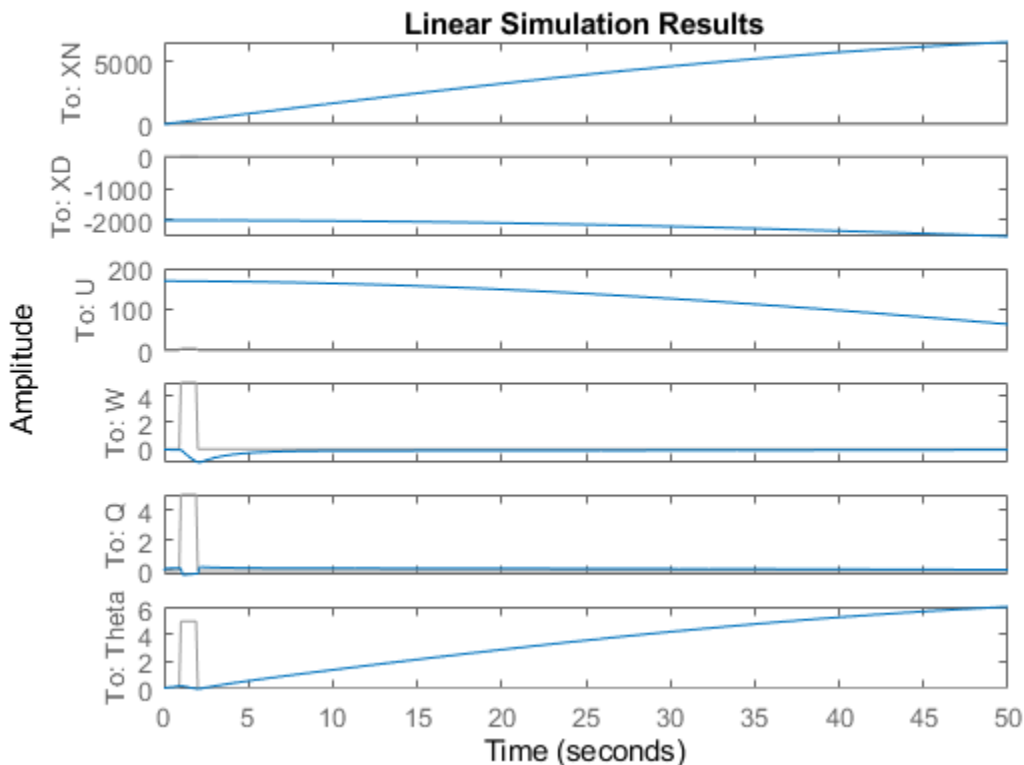
Validating Static Stability with Dynamic Response

With the linear state-space model constructed, you can plot the dynamic behavior of the system.

To verify the static stability results with the dynamic behavior of the system, plot the states space model against the initial conditions.

To induce a perturbation in the system, a 5 degree step for 1 second is added to the elevator signal.

```
x0 = getState(cruiseState, linSys.OutputName);
t = linspace(0, 50, 500);
u = zeros(size(t));
u(t > 1 & t < 2) = 5;
lsim(linSys,u,t,x0)
```



As expected from the static stability analysis, the airspeed and pitch-rate is stable when responding to a small perturbation in the elevator.

Isolating the Elevator-Pitch Response

In addition to the static stability verification, isolating the control surfaces to their intended dynamic response can help design controllers specific to the individual surfaces.

In this case, there is only a single control surface, the elevator.

The elevator controls the pitch response of the aircraft. To show a pitch response, isolate the elevator input to the pitch angle to elevator transfer function.

```
linSysElevatorTF = tf(linSys(6,1))
linSysElevatorTF =
```

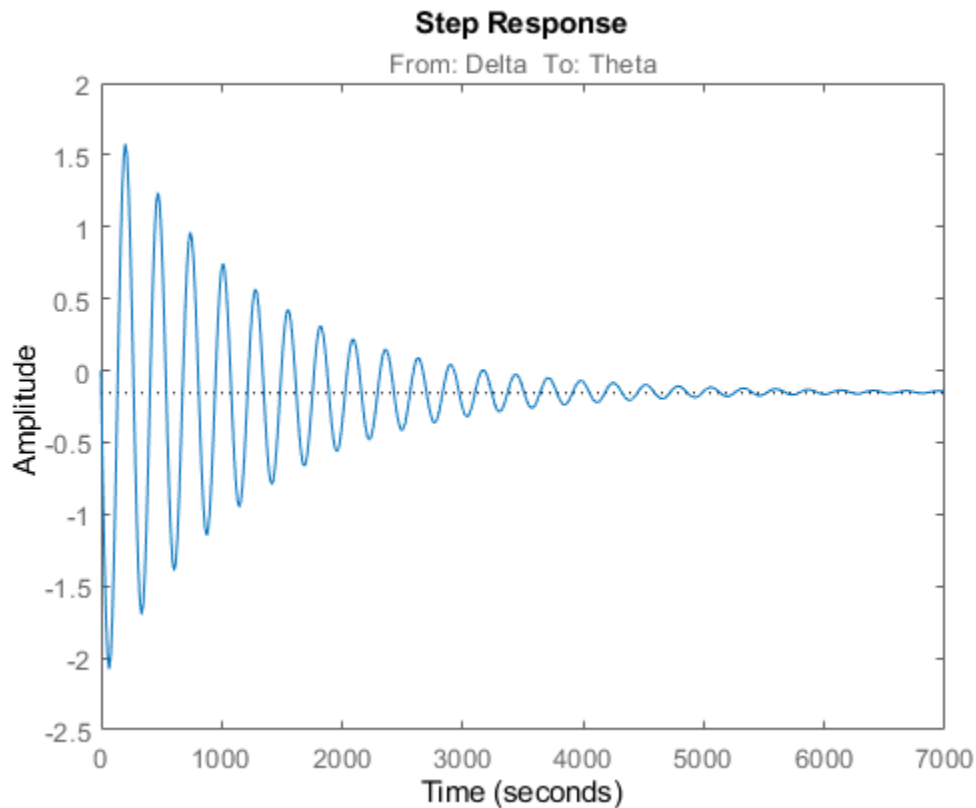
```

From input "Delta" to output "Theta":
      -2.321 s^3 - 0.7222 s^2 - 0.001232 s - 8.935e-09
-----
s^5 + 26.75 s^4 + 15.19 s^3 + 0.03932 s^2 + 0.008227 s + 5.712e-08

```

Continuous-time transfer function.

```
step(linSysElevatorTF)
```



As can be seen by the step plot, the pitch response to elevator input has an undesirable oscillatory nature and large steady-state error.

By adding a PID feedback controller to the elevator input, a much more desirable pitch response can be achieved.

```
C = pidtune(linSysElevatorTF, "PID")
```

```
C =
```

$$K_i * \frac{1}{s}$$

with $K_i = -0.000524$

Continuous-time I-only controller.

```
elevatorFeedback = feedback(linSysElevatorTF * C, 1)
```

elevatorFeedback =

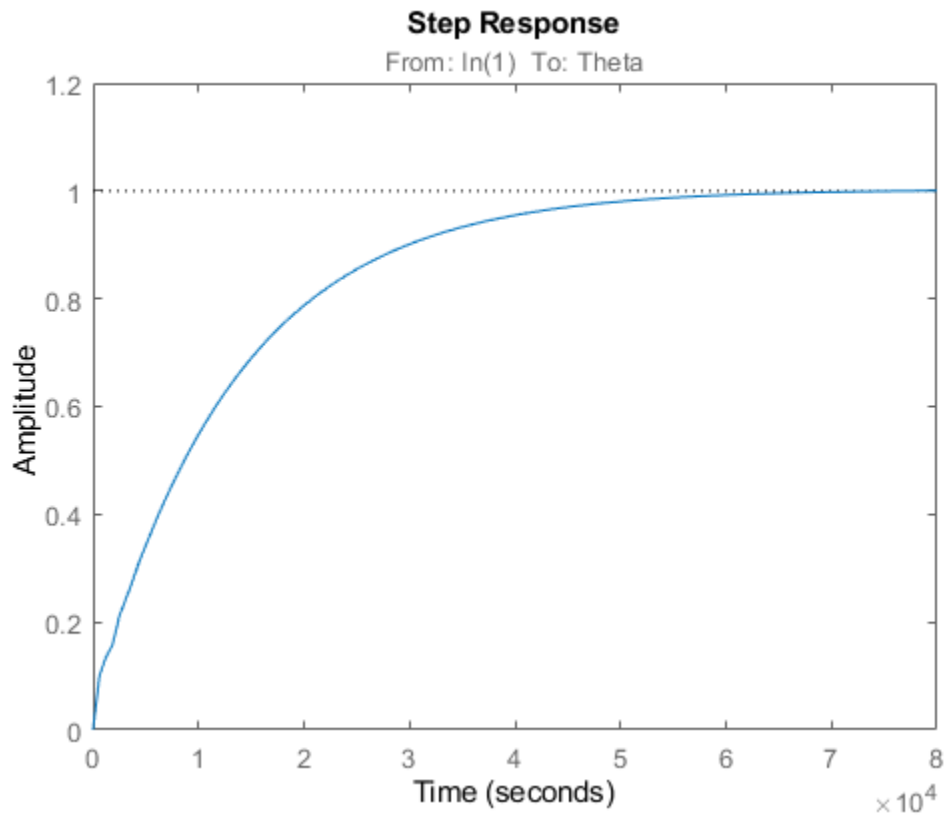
From input to output "Theta":

$$0.001217 s^3 + 0.0003786 s^2 + 6.459e-07 s + 4.684e-12$$

$$s^6 + 26.75 s^5 + 15.19 s^4 + 0.04053 s^3 + 0.008605 s^2 + 7.03e-07 s + 4.684e-12$$

Continuous-time transfer function.

step(elevatorFeedback)



Customize Fixed-Wing Aircraft with Additional Aircraft States

This example shows how to construct and define a custom state for a fixed-wing aircraft.

This example describes:

- Defining custom states and when they might be used.
- Creating a basic custom state.
- Creating an advanced custom state.
- Using a custom state in the analysis of a fixed-wing aircraft.

What are Custom States?

By default, the fixed-wing state object has a fixed set of state values. These include angle of attack, airspeed, altitude, and others.

These states are used within the fixed-wing object to dimensionalize non-dimensional coefficients or provide data to lookup table breakpoints.

However, there are cases where this default set of states does not capture all of the desired states of an aircraft. This is when custom states are used.

By defining a custom state, it is possible to create new state values which can be used within any component of a fixed-wing aircraft.

Defining a Custom State

To create custom states with the `Aero.FixedWing.State` class:

- 1 Define a new class. This class must inherit from the `Aero.FixedWing.State`.
- 2 Define custom states by adding new dependent properties to the class.
- 3 Define the `get.State` method in the custom state class.

Below is a simple example state where the custom state class, `MyState`, is defined with a custom state value, `MyValue`.

The `get` methods of dependent properties can access any other property on the state. In this case, `MyValue` uses ground forward speed, `U`.

```
classdef MyState < Aero.FixedWing.State
    properties (Dependent)
        MyValue
    end

    methods
        function value = get.MyValue(obj)
            value = obj.U * 10;
        end
    end
end
```

A more advanced example of the custom state is the De Havilland Beaver aircraft model [1] which uses a number of custom states to dimensionalize its coefficients. This custom state can be seen as "astDehavillandBeaverState" below.

```

classdef astDehavillandBeaverState < Aero.FixedWing.State

    properties (Dependent)
        Alpha2
        Alpha3
        Beta2
        Beta3

        b2V
        cV
        qcV
        pb2V
        rb2V
        betab2V

        AileronAlpha
        FlapAlpha
        ElevatorBeta2
        RudderAlpha
    end

    methods
        function value = get.Alpha2(obj)
            value = obj.Alpha ^ 2;
        end
        function value = get.Alpha3(obj)
            value = obj.Alpha ^ 3;
        end
        function value = get.Beta2(obj)
            value = obj.Beta ^ 2;
        end
        function value = get.Beta3(obj)
            value = obj.Beta ^ 3;
        end
        end

        function value = get.b2V(obj)
            value = 14.6300 / (2*obj.Airspeed);
        end
        function value = get.cV(obj)
            value = 1.5875 / (obj.Airspeed);
        end
        end

        function value = get.qcV(obj)
            value = obj.Q * obj.cV;
        end
        end
        function value = get.pb2V(obj)
            value = obj.P * obj.b2V;
        end
        end
        function value = get.rb2V(obj)
            value = obj.R * obj.b2V;
        end
        end
        function value = get.betab2V(obj)
            value = obj.Beta * obj.b2V;
        end
        end

        function value = get.AileronAlpha(obj)
            value = obj.getState("Aileron") * obj.Alpha;
        end
        end
    end
end

```

```

function value = get.FlapAlpha(obj)
    value = obj.getState("Flap") * obj.Alpha;
end
function value = get.ElevatorBeta2(obj)
    value = obj.getState("Elevator") * obj.Beta2;
end
function value = get.RudderAlpha(obj)
    value = obj.getState("Rudder") * obj.Alpha;
end
end
end
end

```

This custom state not only directly uses the pre-defined state properties from the fixed-wing state, but also uses the `getState` method to extract the control surface deflection angles. Any combination of states or methods can be used in the `get` methods for custom states.

Using a Custom State

With the custom state defined, use the custom state in the analysis methods.

```

[beaver, cruise] = astDehavillandBeaver()

beaver =
    FixedWing with properties:

        ReferenceArea: 23.2300
        ReferenceSpan: 14.6300
        ReferenceLength: 1.5875
        Coefficients: [1x1 Aero.FixedWing.Coefficient]
        DegreesOfFreedom: "6DOF"
        Surfaces: [1x3 Aero.FixedWing.Surface]
        Thrusts: [1x1 Aero.FixedWing.Thrust]
        AspectRatio: 9.2138
        UnitSystem: "Metric"
        AngleSystem: "Radians"
        TemperatureSystem: "Kelvin"
        Properties: [1x1 Aero.Aircraft.Properties]

cruise =
    astDehavillandBeaverState with properties:

        Alpha2: 0.0209
        Alpha3: 0.0030
        Beta2: 2.1609e-04
        Beta3: -3.1765e-06
        b2V: 0.1642
        cV: 0.0356
        qcV: 1.0159e-22
        pb2V: -1.3994e-20
        rb2V: 4.9110e-20
        betab2V: -0.0024
        AileronAlpha: 0.0013
        FlapAlpha: 0
        ElevatorBeta2: -9.1838e-06
        RudderAlpha: -0.0066
        Alpha: 0.1444
        Beta: -0.0147

```

```

AlphaDot: 0
BetaDot: 0
Mass: 2.2882e+03
Inertia: [3x3 table]
CenterOfGravity: [0 0 0]
CenterOfPressure: [0 0 0]
AltitudeMSL: 2202
GroundHeight: 0
XN: 0
XE: 0
XD: -2202
U: 45
V: 0
W: 0
Phi: 0
Theta: 0.1444
Psi: 0
P: -8.5200e-20
Q: 2.8500e-21
R: 2.9900e-19
Weight: 2.2448e+04
AltitudeAGL: 2202
Airspeed: 44.5365
GroundSpeed: 45
MachNumber: 0.1339
BodyVelocity: [44.0682 -0.6547 6.4080]
GroundVelocity: [45 0 0]
Ur: 44.0682
Vr: -0.6547
Wr: 6.4080
FlightPathAngle: 0
CourseAngle: 0
InertialToBodyMatrix: [3x3 double]
BodyToInertialMatrix: [3x3 double]
BodyToWindMatrix: [3x3 double]
WindToBodyMatrix: [3x3 double]
DynamicPressure: 998.1851
Environment: [1x1 Aero.Aircraft.Environment]
UnitSystem: "Metric"
AngleSystem: "Radians"
TemperatureSystem: "Kelvin"
ControlStates: [1x5 Aero.Aircraft.ControlState]
OutOfRangeAction: "Limit"
DiagnosticAction: "Warning"
Properties: [1x1 Aero.Aircraft.Properties]

```

`cruise.Alpha2`

`ans = 0.0209`

`[F, M] = forcesAndMoments(beaver, cruise)`

`F = 3x1`
`103 ×`

```

0.7116
-0.2185

```

2.8976

M = 3×1
10³ ×

0.0579
1.6427
0.1933

dydt = nonlinearDynamics(beaver, cruise)

dydt = 12×1

44.5317
0
-6.4754
0.3110
-0.0955
1.2663
0.0104
0.2371
0.0174
-0.0000
⋮

[stability, derivatives] = staticStability(beaver, cruise)

stability=6×8 table

	U	V	W	Alpha	Beta	P	Q	R
FX	"Stable"	" "	" "	" "	" "	" "	" "	" "
FY	" "	"Stable"	" "	" "	" "	" "	" "	" "
FZ	" "	" "	"Stable"	" "	" "	" "	" "	" "
L	" "	" "	" "	" "	"Stable"	"Stable"	" "	" "
M	"Stable"	" "	" "	"Stable"	" "	" "	"Stable"	" "
N	" "	" "	" "	" "	"Stable"	" "	" "	"S

derivatives=6×8 table

	U	V	W	Alpha	Beta	P	Q	R
FX	-30.646	-0.94341	656.72	29138	-42.007	0	-557.74	
FY	-9.8123	-65.493	-14.105	-558.71	-2917.1	-472.26	0	139
FZ	-456.65	2.3887	-2888.1	-1.2435e+05	106.36	0	-2469.7	
L	-3.4499	-470.72	-6.295	-255.3	-20967	-28110	0	944
M	217.97	-17.9	-988.08	-44940	-797.04	0	-20417	-188
N	9.3412	51.579	1.3583	0.002102	2297.4	-8831.5	1928.7	-6

References

- 1 Rauw, M.O.: "A Simulink Environment for Flight Dynamics and Control analysis - Application to the DHC-2 'Beaver' ". Part I: "Implementation of a model library in Simulink". Part II: "Nonlinear

analysis of the 'Beaver' autopilot". MSc-thesis, Delft University of Technology, Faculty of Aerospace Engineering. Delft, The Netherlands, 1993.

Determine Nonlinear Dynamics and Static Stability of Fixed-Wing Aircraft

This example shows the process of creating and analyzing a fixed-wing aircraft in MATLAB using Cessna C182 geometry and coefficient data.

The data used to create the aircraft is taken from *Airplane Flight Dynamics and Controls* by Jan Roskam [1 on page 5-0].

This example describes:

- Setting up fixed-wing aerodynamic and control surfaces by creating and nesting an elevator control surface and then creating the aileron, rudder, wing, and vertical stabilizer.
- Creating the propulsion models on the fixed-wing aircraft models similar to control surfaces.
- Defining the full aircraft.
- Defining the coefficients on the aircraft.
- Preparing the aircraft for numerical analysis.
- Performing numerical analysis.

Setting Up Fixed-Wing Aerodynamic and Control Surfaces

The `Aero.FixedWing.Surface` class can serve as both an aerodynamic and control surface.

This behavior is controlled by the `Controllable` property on the class.

Setting `Controllable` to `on` creates a control surface and a `ControlState` variable.

Nesting a control surface on an aerodynamic surface mimics the actual construction of the aircraft.

Below, the example creates an elevator control surface and nests it on the horizontal stabilizer.

```
elevator = Aero.FixedWing.Surface()

elevator =
  Surface with properties:
      Surfaces: [1x0 Aero.FixedWing.Surface]
  Coefficients: [1x1 Aero.FixedWing.Coefficient]
  MaximumValue: Inf
  MinimumValue: -Inf
  Controllable: off
      Symmetry: "Symmetric"
  ControlVariables: [0x0 string]
      Properties: [1x1 Aero.Aircraft.Properties]

elevator.MaximumValue = deg2rad(20);
elevator.MinimumValue = deg2rad(-20);
elevator.Properties = Aero.Aircraft.Properties("Name", "Elevator");
elevator.Controllable = "on";
elevator.Coefficients = Aero.FixedWing.Coefficient("StateVariables", "Elevator")
```

```
elevator =
  Surface with properties:
```

```

    Surfaces: [1x0 Aero.FixedWing.Surface]
    Coefficients: [1x1 Aero.FixedWing.Coefficient]
    MaximumValue: 0.3491
    MinimumValue: -0.3491
    Controllable: on
    Symmetry: "Symmetric"
    ControlVariables: "Elevator"
    Properties: [1x1 Aero.Aircraft.Properties]

```

```
horizontalStabilizer = Aero.FixedWing.Surface()
```

```
horizontalStabilizer =
    Surface with properties:
```

```

    Surfaces: [1x0 Aero.FixedWing.Surface]
    Coefficients: [1x1 Aero.FixedWing.Coefficient]
    MaximumValue: Inf
    MinimumValue: -Inf
    Controllable: off
    Symmetry: "Symmetric"
    ControlVariables: [0x0 string]
    Properties: [1x1 Aero.Aircraft.Properties]

```

```
horizontalStabilizer.Surfaces = elevator
```

```
horizontalStabilizer =
    Surface with properties:
```

```

    Surfaces: [1x1 Aero.FixedWing.Surface]
    Coefficients: [1x1 Aero.FixedWing.Coefficient]
    MaximumValue: Inf
    MinimumValue: -Inf
    Controllable: off
    Symmetry: "Symmetric"
    ControlVariables: [0x0 string]
    Properties: [1x1 Aero.Aircraft.Properties]

```

```
horizontalStabilizer.Properties = Aero.Aircraft.Properties("Name", "HorizontalStabilizer")
```

```
horizontalStabilizer =
    Surface with properties:
```

```

    Surfaces: [1x1 Aero.FixedWing.Surface]
    Coefficients: [1x1 Aero.FixedWing.Coefficient]
    MaximumValue: Inf
    MinimumValue: -Inf
    Controllable: off
    Symmetry: "Symmetric"
    ControlVariables: [0x0 string]
    Properties: [1x1 Aero.Aircraft.Properties]

```

Each property on the fixed-wing objects can also be set through Name,Value arguments on construction. This method of creation will be used in the rest of the example.

Next, construct the ailerons, rudder, wing, and vertical stabilizer.

```

aileron = Aero.FixedWing.Surface(...
    "MaximumValue", deg2rad(20), ...
    "MinimumValue", deg2rad(-20), ...
    "Properties"    , Aero.Aircraft.Properties(1, "Name", "Aileron"), ...
    "Controllable", "on", ...
    "Coefficients", Aero.FixedWing.Coefficient("StateVariables", "Aileron"));

rudder = Aero.FixedWing.Surface(...
    "MaximumValue", deg2rad(20), ...
    "MinimumValue", deg2rad(-20), ...
    "Properties"    , Aero.Aircraft.Properties("Name", "Rudder"), ...
    "Controllable", "on", ...
    "Coefficients", Aero.FixedWing.Coefficient("StateVariables", "Rudder"));

wing = Aero.FixedWing.Surface(...
    "Surfaces"    , aileron, ...
    "Properties"   , Aero.Aircraft.Properties("Name", "Wing"));

verticalStabilizer = Aero.FixedWing.Surface(...
    "Surfaces"    , rudder, ...
    "Properties"   , Aero.Aircraft.Properties("Name", "VerticalStabilizer"));

```

Defining Propulsion

Use the `Aero.FixedWing.Thrust` object to create the propulsion models on the fixed-wing aircraft models similar to control surfaces.

The `Aero.FixedWing.Thrust` object is always controllable. It cannot be nested like aerodynamic and control surfaces.

```

propeller = Aero.FixedWing.Thrust(...
    "Properties"    , Aero.Aircraft.Properties("Name","Propeller"), ...
    "Coefficients", Aero.FixedWing.Coefficient("StateVariables", "Propeller"))

propeller =
    Thrust with properties:

        Coefficients: [1x1 Aero.FixedWing.Coefficient]
        MaximumValue: 1
        MinimumValue: 0
        Controllable: on
        Symmetry: "Symmetric"
        ControlVariables: "Propeller"
        Properties: [1x1 Aero.Aircraft.Properties]

```

Constructing the Aircraft

With the aerodynamic surfaces, control surface, and thrust components defined, define the full aircraft.

First, define a separate `Aero.Aircraft.Properties` class for the aircraft. Use this class to keep track of versions on components and which components a given aircraft is using.

All `Aero.FixedWing` and `Aero.Aircraft` classes contain this property.

```

C182Properties = Aero.Aircraft.Properties(...
    "Name"      , "Cessna C182", ...
    "Type"      , "General Aviation", ...
    "Version"   , "1.0", ...
    "Description", "Cessna 182 Example")

C182Properties =
    Properties with properties:

        Name: "Cessna C182"
    Description: "Cessna 182 Example"
        Type: "General Aviation"
        Version: "1.0"

C182 = Aero.FixedWing(...
    "Properties"      , C182Properties, ...
    "UnitSystem"     , "English (ft/s)", ...
    "AngleSystem"    , "Radians", ...
    "TemperatureSystem", "Fahrenheit", ...
    "ReferenceArea"  , 174, ...
    "ReferenceSpan"  , 36, ...
    "ReferenceLength", 4.9, ...
    "Surfaces"       , [wing, horizontalStabilizer, verticalStabilizer], ...
    "Thrusts"        , propeller)

C182 =
    FixedWing with properties:

        ReferenceArea: 174
        ReferenceSpan: 36
        ReferenceLength: 4.9000
        Coefficients: [1x1 Aero.FixedWing.Coefficient]
        DegreesOfFreedom: "6DOF"
            Surfaces: [1x3 Aero.FixedWing.Surface]
            Thrusts: [1x1 Aero.FixedWing.Thrust]
        AspectRatio: 7.4483
        UnitSystem: "English (ft/s)"
        AngleSystem: "Radians"
        TemperatureSystem: "Fahrenheit"
        Properties: [1x1 Aero.Aircraft.Properties]

```

Setting the Aircraft Coefficients

Next, define the coefficients on the aircraft.

These coefficients describe the dynamic behavior of the aircraft. This example defines scalar constant coefficients, which define the linear behavior of the aircraft.

To define non-linear dynamic behavior of a fixed-wing aircraft, define `Simulink.LookupTable` coefficients. `Simulink.LookupTables` are not used in this example. To see an example using `Simulink.LookupTables`, open the “Perform Controls and Static Stability Analysis with Linearized Fixed-Wing Aircraft” on page 5-115 example.

By default, all coefficients are 0.

```

BodyCoefficients = {
    'CD', 'Zero', 0.027;

```

```

'CL', 'Zero', 0.307;
'Cm', 'Zero', 0.04;
'CD', 'Alpha', 0.121;
'CL', 'Alpha', 4.41;
'Cm', 'Alpha', -0.613;
'CD', 'AlphaDot', 0;
'CL', 'AlphaDot', 1.7;
'Cm', 'AlphaDot', -7.27;
'CD', 'Q', 0;
'CL', 'Q', 3.9;
'Cm', 'Q', -12.4;
'CY', 'Beta', -0.393;
'Cl', 'Beta', -0.0923;
'Cn', 'Beta', 0.0587;
'CY', 'P', -0.075;
'Cl', 'P', -0.484;
'Cn', 'P', -0.0278;
'CY', 'R', 0.214;
'Cl', 'R', 0.0798;
'Cn', 'R', -0.0937;
};

```

```
C182 = setCoefficient(C182, BodyCoefficients(:, 1), BodyCoefficients(:, 2), BodyCoefficients(:, 3),
```

Coefficients can be defined on any component on the aircraft. These components can include any `Aero.FixedWing.Surface` or `Aero.FixedWing.Thrust`.

The `setCoefficient` method provides a `Component Name, Value` argument, which takes the coefficients on the desired component name, obviating the need to know exactly where the component is on the aircraft.

Valid component names depend on the `Name` property on the component.

```

AileronCoefficients = {
    'CY', 'Aileron', 0;
    'Cl', 'Aileron', 0.229;
    'Cn', 'Aileron', -0.0504;
};
ElevatorCoefficients = {
    'CY', 'Elevator', 0.187;
    'Cl', 'Elevator', 0.0147;
    'Cn', 'Elevator', -0.0805;
};
RudderCoefficients = {
    'CD', 'Rudder', 0;
    'CL', 'Rudder', 0.43;
    'Cm', 'Rudder', -1.369;
};
PropellerCoefficients = {
    'CD', 'Propeller', -21.1200;
};

```

```

C182 = setCoefficient(C182, AileronCoefficients(:, 1), AileronCoefficients(:, 2), AileronCoefficients(:, 3),
C182 = setCoefficient(C182, ElevatorCoefficients(:, 1), ElevatorCoefficients(:, 2), ElevatorCoefficients(:, 3),
C182 = setCoefficient(C182, RudderCoefficients(:, 1), RudderCoefficients(:, 2), RudderCoefficients(:, 3),
C182 = setCoefficient(C182, PropellerCoefficients(:, 1), PropellerCoefficients(:, 2), PropellerCoefficients(:, 3),

```

Defining the Current State

The fixed-wing aircraft is fully constructed and ready for numerical analysis.

To perform numerical analysis on a fixed-wing aircraft, define an `Aero.FixedWing.State` object.

The `Aero.FixedWing.State` object defines the current state of the `Aero.FixedWing` object at an instance in time. The `Aero.FixedWing.State` is also where dynamic physical properties of the aircraft, including the mass and inertia, are defined.

In this example, we analyze the cruise state.

```
CruiseState = Aero.FixedWing.State(...
    "UnitSystem", "English (ft/s)", ...
    "AngleSystem", "Radians", ...
    "TemperatureSystem", "Fahrenheit", ...
    "Mass", 82.2981, ...
    "U", 220.1, ...
    "AltitudeMSL", 5000);

CruiseState.Inertia.Variables = [
    948, 0, 0 ;
    0 , 1346, 0 ;
    0 , 0 , 1967;
];

CruiseState.CenterOfGravity = [0.264, 0 , 0] .* C182.ReferenceLength;
CruiseState.CenterOfPressure = [0.25, 0, 0] .* C182.ReferenceLength;
CruiseState.Environment = Aero.Aircraft.Environment(...
    "Temperature", 500.839, ...
    "Density", 0.00204834, ...
    "SpeedOfSound", 1097.09, ...
    "Pressure", 84307.3, ...
    "Gravity", 32.2);
```

Setting Up the Control States

In addition to the environment and dynamic physical properties, the `Aero.FixedWing.State` class also holds the current control surface deflections and thrust positions. These positions are held in the `ControlStates` property. Use this class to set up the control states.

By default, this property is empty. Initialize the property from the control surface and thrust information on the aircraft.

To set up these control states, use the `setupControlStates` method below.

```
CruiseState = setupControlStates(CruiseState, C182)
```

```
CruiseState =
    State with properties:

        Alpha: 0
        Beta: 0
        AlphaDot: 0
        BetaDot: 0
        Mass: 82.2981
        Inertia: [3x3 table]
        CenterOfGravity: [1.2936 0 0]
```

```
CenterOfPressure: [1.2250 0 0]
  AltitudeMSL: 5000
  GroundHeight: 0
    XN: 0
    XE: 0
    XD: -5000
    U: 220.1000
    V: 0
    W: 0
  Phi: 0
  Theta: 0
  Psi: 0
  P: 0
  Q: 0
  R: 0
  Weight: 2.6500e+03
  AltitudeAGL: 5000
  Airspeed: 220.1000
  GroundSpeed: 220.1000
  MachNumber: 0.2006
  BodyVelocity: [220.1000 0 0]
  GroundVelocity: [220.1000 0 0]
    Ur: 220.1000
    Vr: 0
    Wr: 0
  FlightPathAngle: 0
  CourseAngle: 0
  InertialToBodyMatrix: [3x3 double]
  BodyToInertialMatrix: [3x3 double]
  BodyToWindMatrix: [3x3 double]
  WindToBodyMatrix: [3x3 double]
  DynamicPressure: 49.6149
  Environment: [1x1 Aero.Aircraft.Environment]
  UnitSystem: "English (ft/s)"
  AngleSystem: "Radians"
  TemperatureSystem: "Fahrenheit"
  ControlStates: [1x4 Aero.Aircraft.ControlState]
  OutOfRangeAction: "Limit"
  DiagnosticAction: "Warning"
  Properties: [1x1 Aero.Aircraft.Properties]
```

Perform this only once per aircraft configuration. If no control surfaces or thrusts have been added or removed to the aircraft, skip this step.

Performing Numerical Analysis

At this point, the aircraft and state are now fully constructed and defined.

A number of numerical analysis methods come with the fixed-wing aircraft, including forces and moments, non-linear dynamics, and static stability.

Forces and Moments

To calculate the forces and moments on the aircraft at an instance in time, use the `forcesAndMoments` method.

These forces and moments are in the aircraft body frame. Coefficients defined in a different frame have the appropriate transformation matrices applied to translate them to the body frame.

```
[F, M] = forcesAndMoments(C182, CruiseState)
```

```
F = 3×1
```

```
-233.0908
      0
   -0.3300
```

```
M = 3×1
```

```
103 ×
```

```
      0
   1.8739
      0
```

Nonlinear Dynamics

To calculate the aircraft dynamic behavior, use the `nonlinearDynamics` method.

The `nonlinearDynamics` method returns a vector of the rates of change of the selected degrees of freedom on the aircraft. The size of the vector depends on the degrees of freedom. To calculate the aircraft dynamic behavior over time, use the vector in conjunction with an ode solver, such as `ode45`.

To quickly iterate between the fidelities of different aircraft designs, or trim unnecessary states from the output vector, change the selected degrees of freedom. These rates of change are defined below:

```
disp(load("astFixedWingDOFtable.mat").DOFtable)
```

	PM4	PM6	3DOF	6DOF
	—	—	—	—
dXN /dt	"X"	"X"	"X"	"X"
dXE /dt	" "	"X"	" "	"X"
dXD /dt	"X"	"X"	"X"	"X"
dU /dt	"X"	"X"	"X"	"X"
dV /dt	" "	"X"	" "	"X"
dW /dt	"X"	"X"	"X"	"X"
dP /dt	" "	" "	" "	"X"
dQ /dt	" "	" "	"X"	"X"
dR /dt	" "	" "	" "	"X"
dPhi /dt	" "	" "	" "	"X"
dTheta /dt	" "	" "	"X"	"X"
dPsi /dt	" "	" "	" "	"X"

```
dydt = nonlinearDynamics(C182, CruiseState)
```

```
dydt = 12×1
```

```
220.1000
      0
      0
   -2.8323
      0
   -0.0040
```

```

0
1.3922
0
0
:

```

Static Stability

Static stability is the tendency of an aircraft to return to its original state after a small perturbation from an initial state. It is an important feature of aircraft for civilian use and reduces the need for complex controllers to maintain dynamic stability. Under some conditions, aircraft that require advanced maneuverability might opt for static instability.

The `Aero.FixedWing` object `staticStability` method calculates from changes in forces and moments due to perturbations at the current state of an aircraft.

The method compares the perturbations against a predefined set of criteria as less-than, greater-than, or equal-to zero. You can also specify custom criteria. The method then evaluates the static stability as:

- If the criteria is satisfied, then the perturbation is statically stable.
- If the criteria is not satisfied, then the perturbation is statically unstable.
- If the perturbation is 0, the perturbation is statically neutral.

The `staticStability` method does not perform a requirements-based analysis. Only use this method in the preliminary design phase.

```
[stability, derivatives] = staticStability(C182, CruiseState)
```

stability=6×8 table

	U	V	W	Alpha	Beta	P	Q	
FX	"Stable"	" "	" "	" "	" "	" "	" "	" "
FY	" "	"Stable"	" "	" "	" "	" "	" "	" "
FZ	" "	" "	"Stable"	" "	" "	" "	" "	" "
L	" "	" "	" "	" "	"Stable"	"Stable"	" "	" "
M	"Stable"	" "	" "	"Stable"	" "	" "	"Stable"	" "
N	" "	" "	" "	" "	"Stable"	" "	" "	"S

derivatives=6×8 table

	U	V	W	Alpha	Beta	P	Q	
FX	-2.118	-5.4001e-08	7.2955	1606.1	-0.0023309	0		
FY	0	-15.415	0	0	-3392.8	-647.47		
FZ	-24.083	-5.9117e-07	-174.03	-38305	-0.026503	0	-3366	
L	0	-130.33	0	0	-28686	-1.5042e+05		
M	17.028	4.5475e-07	-105.88	-23303	0.018739	0	-5.2223e+05	
N	0	83.944	0	0	18476	-8595.5		

References

- 1 Roskam, J., "Airplane Flight Dynamics and Automatic Flight Controls (Part 1)", DAR Corporation, 2003.

Modeling Satellite Constellations using Ephemeris Data

This example demonstrates how to add time-stamped ephemeris data for a constellation of 24 satellites (similar to ESA Galileo GNSS constellation) to a satellite scenario for access analysis. The example uses data generated by the Aerospace Blockset **Orbit Propagator** block. For more information, see the Aerospace Blockset example *Constellation Modeling with the Orbit Propagator Block*.

The **satelliteScenario** object supports loading previously generated, time-stamped satellite ephemeris data into a scenario from a **timeseries** or **timetable** object. An ephemeris is a table containing position (and optionally velocity) state information of a satellite during a given period of time. Ephemeris data used to add satellites to the scenario object is interpolated via the **makima** interpolation method to align with the scenario time steps. This allows you to incorporate data generated by a Simulink model into either a new or existing satelliteScenario.

Define Mission Parameters and Constellation Initial Conditions

Specify a start date and duration for the mission. This example uses MATLAB structures to organize mission data. These structures make accessing data later in the example more intuitive. They also help declutter the global base workspace.

```
mission.StartDate = datetime(2020, 11, 30, 22, 23, 24);
mission.Duration = hours(24);
```

The constellation in this example is a Walker-Delta constellation modeled similar to the ESA Galileo GNSS (Global navigation satellite system) constellation. The constellation consists of 24 satellites in medium Earth orbit (MEO). The satellites' Keplerian orbital elements at the mission start date epoch are:

```
mission.ConstellationDefinition = table( ...
    23222e3 * ones(24,1), ... % Semi-major axis (m)
    0.0005 * ones(24,1), ... % Eccentricity
    56 * ones(24,1), ... % Inclination (deg)
    350 * ones(24,1), ... % Right ascension of the ascending node (deg)
    sort(repmat([0 120 240], 1,8))', ... % Argument of periapsis (deg)
    [0:45:315, 15:45:330, 30:45:345]', ... % True anomaly (deg)
    'VariableNames', ["a (m)", "e", "i (deg)", "Ω (deg)", "ω (deg)", "ν (deg)"]);
mission.ConstellationDefinition
```

```
ans=24x6 table
    a (m)         e         i (deg)      Ω (deg)      ω (deg)      ν (deg)
    _____  _____  _____  _____  _____  _____
    2.3222e+07    0.0005     56         350         0           0
    2.3222e+07    0.0005     56         350         0           45
    2.3222e+07    0.0005     56         350         0           90
    2.3222e+07    0.0005     56         350         0          135
    2.3222e+07    0.0005     56         350         0          180
    2.3222e+07    0.0005     56         350         0          225
    2.3222e+07    0.0005     56         350         0          270
    2.3222e+07    0.0005     56         350         0          315
    2.3222e+07    0.0005     56         350        120           15
    2.3222e+07    0.0005     56         350        120           60
    2.3222e+07    0.0005     56         350        120          105
    2.3222e+07    0.0005     56         350        120          150
    2.3222e+07    0.0005     56         350        120          195
```

```

2.3222e+07    0.0005    56    350    120    240
2.3222e+07    0.0005    56    350    120    285
2.3222e+07    0.0005    56    350    120    330
⋮

```

Load Ephemeris Timeseries Data

The timeseries objects contain position and velocity data for all 24 satellites in the constellation. The data is referenced in the International Terrestrial Reference frame (ITRF), which is an Earth-centered Earth-fixed (ECEF) coordinate system. The data was generated using the Aerospace Blockset **Orbit Propagator** block. For more information, see the Aerospace Blockset example *Constellation Modeling with the Orbit Propagator Block*.

```

mission.Ephemeris = load("SatelliteScenarioEphemerisData.mat", "TimeseriesPosITRF", "TimeseriesVelITRF");
mission.Ephemeris.TimeseriesPosITRF

```

```

timeseries

Common Properties:
    Name: ''
    Time: [79x1 double]
    TimeInfo: [1x1 tsdata.timemetadata]
    Data: [24x3x79 double]
    DataInfo: [1x1 tsdata.datametadata]

```

More properties, Methods

```

mission.Ephemeris.TimeseriesVelITRF

```

```

timeseries

Common Properties:
    Name: ''
    Time: [79x1 double]
    TimeInfo: [1x1 tsdata.timemetadata]
    Data: [24x3x79 double]
    DataInfo: [1x1 tsdata.datametadata]

```

More properties, Methods

Load the Satellite Ephemerides into a satelliteScenario Object

Create a satellite scenario object for the analysis.

```

scenario = satelliteScenario(mission.StartDate, mission.StartDate + hours(24), 60);

```

Use the **satellite** method to add all 24 satellites to the satellite scenario from the ECEF position and velocity timeseries objects. This example uses position and velocity information; however satellites can also be added from position data only and velocity states are then estimated. Available coordinate frames for Name-Value pair `CoordinateFrame` are "ECEF", "Inertial", and "Geographic". If the timeseries object contains a value for `ts.TimeInfo.StartDate`, the method uses that value as the epoch for the timeseries object. If no `StartDate` is defined, the method uses the scenario start date by default.

```

sat = satellite(scenario, mission.Ephemeris.TimeseriesPosITRF, mission.Ephemeris.TimeseriesVelITRF, ...
    "CoordinateFrame", "ecef", "Name", "GALILEO " + (1:24))

```

```
sat =
  1x24 Satellite array with properties:
```

```

  Name
  ID
  ConicalSensors
  Gimbals
  Transmitters
  Receivers
  Accesses
  GroundTrack
  Orbit
  OrbitPropagator
  MarkerColor
  MarkerSize
  ShowLabel
  LabelFontSize
  LabelFontColor
```

```
disp(scenario)
```

```
satelliteScenario with properties:
```

```

  StartTime: 30-Nov-2020 22:23:24
  StopTime: 01-Dec-2020 22:23:24
  SampleTime: 60
  Viewers: [0x0 matlabshared.satellitescenario.Viewer]
  Satellites: [1x24 matlabshared.satellitescenario.Satellite]
  GroundStations: []
  AutoShow: 1
```

Alternatively, satellites can also be added as ephemerides to the satellite scenario as a MATLAB **timetable**, **table**, or **tscollection**. For example, a **timetable** containing the first 3 satellites of the position **timeseries** object in the previous section, formatted for use with **satelliteScenario** objects is shown below.

- Satellites are represented by variables (column headers).
- Each row contains a position vector associated with the row's **Time** property.

```
timetable(...
datetime(getabstime(mission.Ephemeris.TimeseriesPosITRF)), ...
squeeze(mission.Ephemeris.TimeseriesPosITRF.Data(1,:,:))', ...
squeeze(mission.Ephemeris.TimeseriesPosITRF.Data(2,:,:))', ...
squeeze(mission.Ephemeris.TimeseriesPosITRF.Data(3,:,:))',...
'VariableNames', ["Satellite_1", "Satellite_2", "Satellite_3"])
```

```
ans=79x3 timetable
```

Time	Satellite_1	Satellite_2	Satellite_3
30-Nov-2020 22:23:24	1.4317e+07	-1.7969e+07	-3.2957e+06
30-Nov-2020 22:23:34	1.4326e+07	-1.7968e+07	-3.2607e+06
30-Nov-2020 22:24:26	1.4367e+07	-1.7966e+07	-3.0856e+06
30-Nov-2020 22:28:44	1.4562e+07	-1.7939e+07	-2.2062e+06
30-Nov-2020 22:40:57	1.4983e+07	-1.7724e+07	3.0748e+05
30-Nov-2020 22:54:44	1.5245e+07	-1.7219e+07	3.1374e+06
30-Nov-2020 23:08:36	1.5308e+07	-1.6416e+07	5.9118e+06

30-Nov-2020	23:24:15	1.5183e+07	-1.5144e+07	8.8865e+06	1.4218e+07	-1.4887e+07
30-Nov-2020	23:40:33	1.4888e+07	-1.3412e+07	1.1718e+07	1.2964e+07	2.6318e+07
30-Nov-2020	23:57:25	1.4477e+07	-1.1213e+07	1.4269e+07	1.1748e+07	5.6176e+07
01-Dec-2020	00:15:24	1.3994e+07	-8.4611e+06	1.6479e+07	1.0588e+07	8.8233e+07
01-Dec-2020	00:33:57	1.3527e+07	-5.2723e+06	1.8119e+07	9.5707e+06	1.2021e+07
01-Dec-2020	00:53:11	1.3142e+07	-1.7143e+06	1.9066e+07	8.7131e+06	1.5075e+07
01-Dec-2020	01:12:46	1.2901e+07	2.0218e+06	1.9203e+07	8.0192e+06	1.7771e+07
01-Dec-2020	01:32:20	1.2826e+07	5.7119e+06	1.8499e+07	7.449e+06	1.9927e+07
01-Dec-2020	01:51:55	1.2899e+07	9.1955e+06	1.6986e+07	6.9227e+06	2.1452e+07
:						

Set Graphical Properties on the Satellites

Viewer windows with many satellites can become crowded and difficult to read. To keep the window readable, manually control graphical properties of the scenario elements.

Hide the satellite labels and ground tracks.

```
set(sat, "ShowLabel", false);
hide([sat(:).GroundTrack]);
```

Set satellite in the same orbital plane to have the same orbit color.

```
set(sat(1:8), "MarkerColor", "red");
set(sat(9:16), "MarkerColor", "blue");
set(sat(17:24), "MarkerColor", "green");
orbit = [sat(:).Orbit];
set(orbit(1:8), "LineColor", "red");
set(orbit(9:16), "LineColor", "blue");
set(orbit(17:24), "LineColor", "green");
```

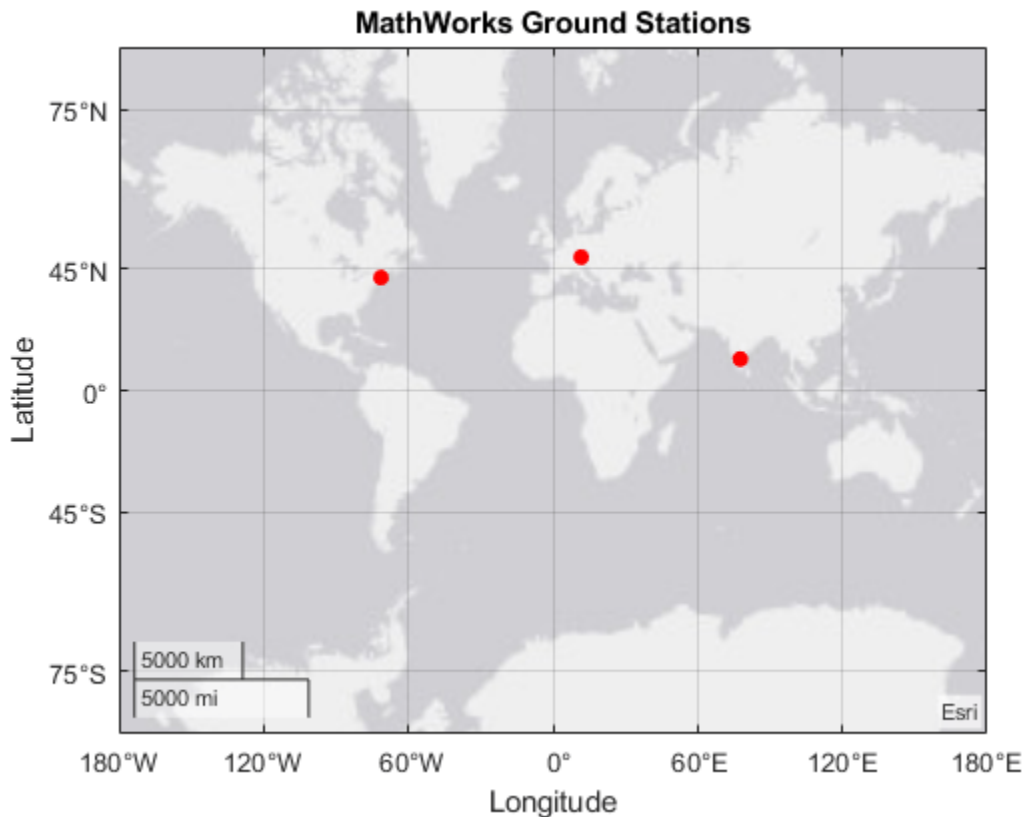
Add Ground Stations to Scenario

To provide accurate positioning data, a location on Earth must have access to at least 4 satellites in the constellation at any given time. In this example, use three MathWorks locations to compare total constellation access over the 1 day analysis window to different regions of Earth:

- MathWorks headquarters in Natick, Massachusetts, USA (42.30048°, -71.34908°)
- MathWorks München in Ismaning (near München), Germany (48.23206°, 11.68445°)
- MathWorks Bangalore in Bangalore, India (12.94448°, 77.69256°)

```
gsUS = groundStation(scenario, 42.30048, -71.34908, ...
    "MinElevationAngle", 10, "Name", "MW Natick");
gsDE = groundStation(scenario, 48.23206, 11.68445, ...
    "MinElevationAngle", 10, "Name", "MW Munchen");
gsIN = groundStation(scenario, 12.94448, 77.69256, ...
    "MinElevationAngle", 10, "Name", "MW Bangalore");

figure
geoscat([gsUS.Latitude gsDE.Latitude gsIN.Latitude], ...
    [gsUS.Longitude gsDE.Longitude gsIN.Longitude], "red", "filled")
geolimits([-75 75], [-180 180])
title("MathWorks Ground Stations")
```



Compute Ground Station to Satellite Access (Line-of-Sight Visibility)

Calculate line-of-sight access between the ground stations and each individual satellite using the `access` method.

```
for idx = 1:numel(sat)
    access(gsUS, sat(idx));
    access(gsDE, sat(idx));
    access(gsIN, sat(idx));
end
accessUS = [gsUS(:).Accesses];
accessDE = [gsDE(:).Accesses];
accessIN = [gsIN(:).Accesses];
```

Set access colors to match orbital plane colors assigned earlier in the example.

```
set(accessUS(1:8), "LineColor", "red");
set(accessUS(9:16), "LineColor", "blue");
set(accessUS(17:24), "LineColor", "green");

set(accessDE(1:8), "LineColor", "red");
set(accessDE(9:16), "LineColor", "blue");
set(accessDE(17:24), "LineColor", "green");

set(accessIN(1:8), "LineColor", "red");
set(accessIN(9:16), "LineColor", "blue");
set(accessIN(17:24), "LineColor", "green");
```


View the full access table between each ground station and all satellites in the constellation as tables. Sort the access intervals by interval start time. Satellites added from ephemeris data do not display values for StartOrbit and EndOrbit.

```
intervalsUS = accessIntervals(accessUS);
intervalsUS = sortrows(intervalsUS, "StartTime", "ascend")
```

intervalsUS=52x8 table

Source	Target	IntervalNumber	StartTime	EndTime
"MW Natick"	"GALILEO 1"	1	30-Nov-2020 22:23:24	01-Dec-2020 01:40:24
"MW Natick"	"GALILEO 2"	1	30-Nov-2020 22:23:24	01-Dec-2020 00:08:24
"MW Natick"	"GALILEO 3"	1	30-Nov-2020 22:23:24	30-Nov-2020 22:34:24
"MW Natick"	"GALILEO 12"	1	30-Nov-2020 22:23:24	30-Nov-2020 23:35:24
"MW Natick"	"GALILEO 13"	1	30-Nov-2020 22:23:24	30-Nov-2020 22:47:24
"MW Natick"	"GALILEO 18"	1	30-Nov-2020 22:23:24	01-Dec-2020 01:51:24
"MW Natick"	"GALILEO 19"	1	30-Nov-2020 22:23:24	01-Dec-2020 00:13:24
"MW Natick"	"GALILEO 20"	1	30-Nov-2020 22:23:24	30-Nov-2020 22:27:24
"MW Natick"	"GALILEO 11"	1	30-Nov-2020 22:38:24	01-Dec-2020 00:00:24
"MW Natick"	"GALILEO 17"	1	30-Nov-2020 22:47:24	01-Dec-2020 03:19:24
"MW Natick"	"GALILEO 8"	1	30-Nov-2020 23:09:24	01-Dec-2020 03:15:24
"MW Natick"	"GALILEO 7"	1	01-Dec-2020 00:28:24	01-Dec-2020 04:55:24
"MW Natick"	"GALILEO 24"	1	01-Dec-2020 00:29:24	01-Dec-2020 04:40:24
"MW Natick"	"GALILEO 6"	1	01-Dec-2020 01:54:24	01-Dec-2020 06:41:24
"MW Natick"	"GALILEO 23"	1	01-Dec-2020 02:04:24	01-Dec-2020 05:52:24
"MW Natick"	"GALILEO 5"	1	01-Dec-2020 03:30:24	01-Dec-2020 08:25:24
:				

```
intervalsDE = accessIntervals(accessDE);
intervalsDE = sortrows(intervalsDE, "StartTime", "ascend")
```

intervalsDE=51x8 table

Source	Target	IntervalNumber	StartTime	EndTime
"MW Munchen"	"GALILEO 2"	1	30-Nov-2020 22:23:24	01-Dec-2020 02:01:24
"MW Munchen"	"GALILEO 3"	1	30-Nov-2020 22:23:24	01-Dec-2020 00:20:24
"MW Munchen"	"GALILEO 4"	1	30-Nov-2020 22:23:24	30-Nov-2020 22:40:24
"MW Munchen"	"GALILEO 19"	1	30-Nov-2020 22:23:24	01-Dec-2020 00:42:24
"MW Munchen"	"GALILEO 20"	1	30-Nov-2020 22:23:24	30-Nov-2020 23:35:24
"MW Munchen"	"GALILEO 10"	1	30-Nov-2020 22:38:24	30-Nov-2020 22:49:24
"MW Munchen"	"GALILEO 18"	1	30-Nov-2020 22:42:24	01-Dec-2020 01:37:24
"MW Munchen"	"GALILEO 9"	1	30-Nov-2020 22:44:24	01-Dec-2020 00:43:24
"MW Munchen"	"GALILEO 1"	1	30-Nov-2020 22:55:24	01-Dec-2020 03:37:24
"MW Munchen"	"GALILEO 16"	1	30-Nov-2020 23:24:24	01-Dec-2020 02:15:24
"MW Munchen"	"GALILEO 17"	1	01-Dec-2020 00:13:24	01-Dec-2020 02:19:24
"MW Munchen"	"GALILEO 15"	1	01-Dec-2020 00:18:24	01-Dec-2020 03:45:24
"MW Munchen"	"GALILEO 8"	1	01-Dec-2020 00:36:24	01-Dec-2020 05:07:24
"MW Munchen"	"GALILEO 14"	1	01-Dec-2020 01:24:24	01-Dec-2020 05:17:24
"MW Munchen"	"GALILEO 24"	1	01-Dec-2020 01:57:24	01-Dec-2020 02:36:24
"MW Munchen"	"GALILEO 7"	1	01-Dec-2020 02:16:24	01-Dec-2020 06:29:24
:				

```
intervalsIN = accessIntervals(accessIN);
intervalsIN = sortrows(intervalsIN, "StartTime", "ascend")
```

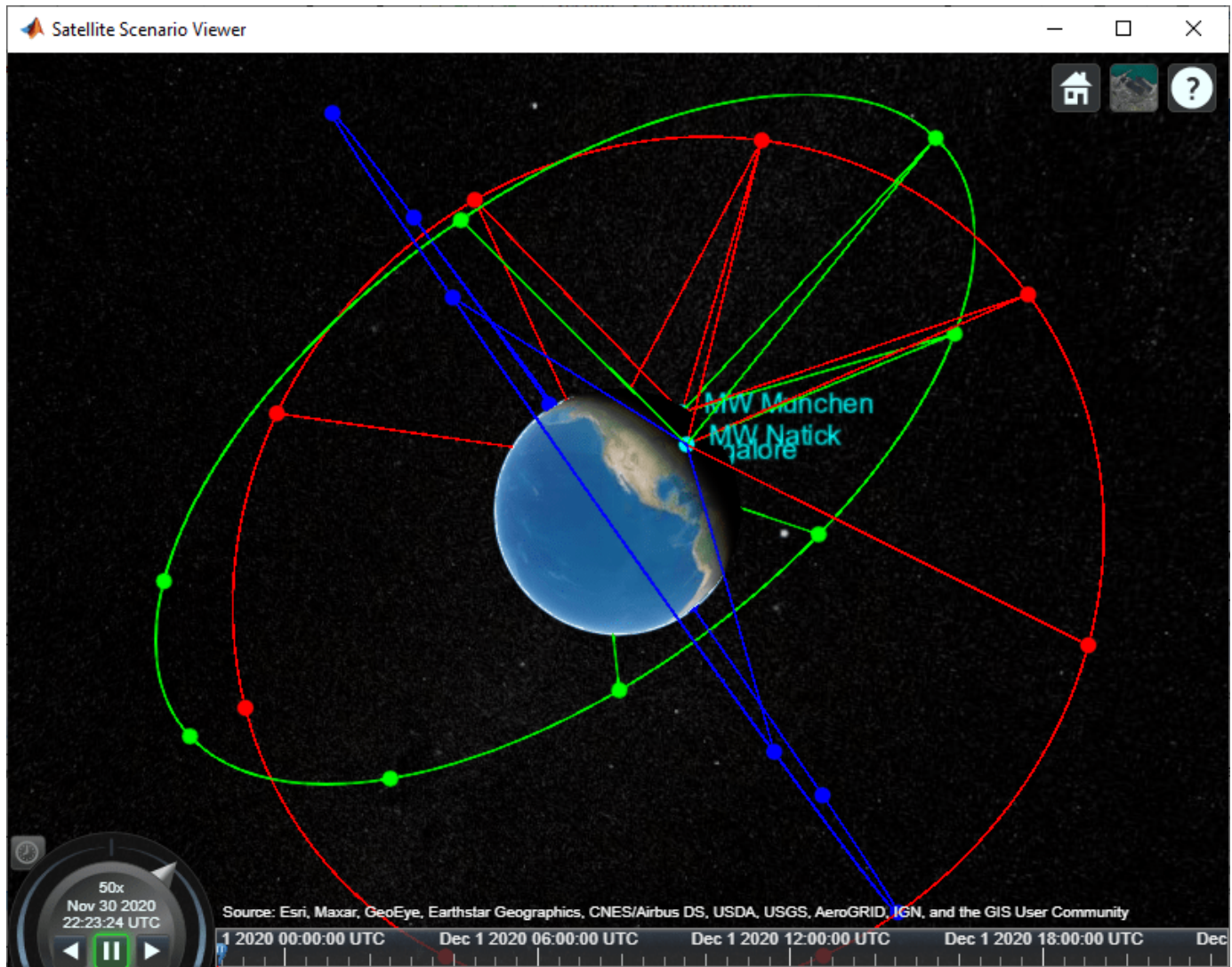
intervalsIN=45x8 table
Source

Source	Target	IntervalNumber	StartTime	EndTime
"MW Bangalore"	"GALILEO 3"	1	30-Nov-2020 22:23:24	01-Dec-2020 02:30:24
"MW Bangalore"	"GALILEO 4"	1	30-Nov-2020 22:23:24	01-Dec-2020 01:00:24
"MW Bangalore"	"GALILEO 5"	1	30-Nov-2020 22:23:24	30-Nov-2020 23:15:24
"MW Bangalore"	"GALILEO 9"	1	30-Nov-2020 22:23:24	01-Dec-2020 00:55:24
"MW Bangalore"	"GALILEO 10"	1	30-Nov-2020 22:23:24	30-Nov-2020 23:15:24
"MW Bangalore"	"GALILEO 16"	1	30-Nov-2020 22:23:24	01-Dec-2020 02:45:24
"MW Bangalore"	"GALILEO 21"	1	30-Nov-2020 22:23:24	30-Nov-2020 23:00:24
"MW Bangalore"	"GALILEO 22"	1	30-Nov-2020 22:23:24	30-Nov-2020 22:29:24
"MW Bangalore"	"GALILEO 15"	1	30-Nov-2020 23:36:24	01-Dec-2020 05:15:24
"MW Bangalore"	"GALILEO 2"	1	30-Nov-2020 23:44:24	01-Dec-2020 04:00:24
"MW Bangalore"	"GALILEO 21"	2	01-Dec-2020 01:15:24	01-Dec-2020 04:15:24
"MW Bangalore"	"GALILEO 1"	1	01-Dec-2020 01:20:24	01-Dec-2020 05:20:24
"MW Bangalore"	"GALILEO 14"	1	01-Dec-2020 01:29:24	01-Dec-2020 07:30:24
"MW Bangalore"	"GALILEO 20"	1	01-Dec-2020 02:04:24	01-Dec-2020 05:50:24
"MW Bangalore"	"GALILEO 8"	1	01-Dec-2020 02:56:24	01-Dec-2020 06:30:24
"MW Bangalore"	"GALILEO 19"	1	01-Dec-2020 03:20:24	01-Dec-2020 07:30:24
:				

View the Satellite Scenario

Open a 3-D viewer window of the scenario. The viewer window contains all 24 satellites and the three ground stations defined earlier in this example. A line is drawn between each ground station and satellite during their corresponding access intervals.

```
viewer3D = satelliteScenarioViewer(scenario);
```



Compare Access Between Ground Stations

Calculate access status between each satellite and ground station using the `accessStatus` method. Plot cumulative access for each ground station over the one day analysis window.

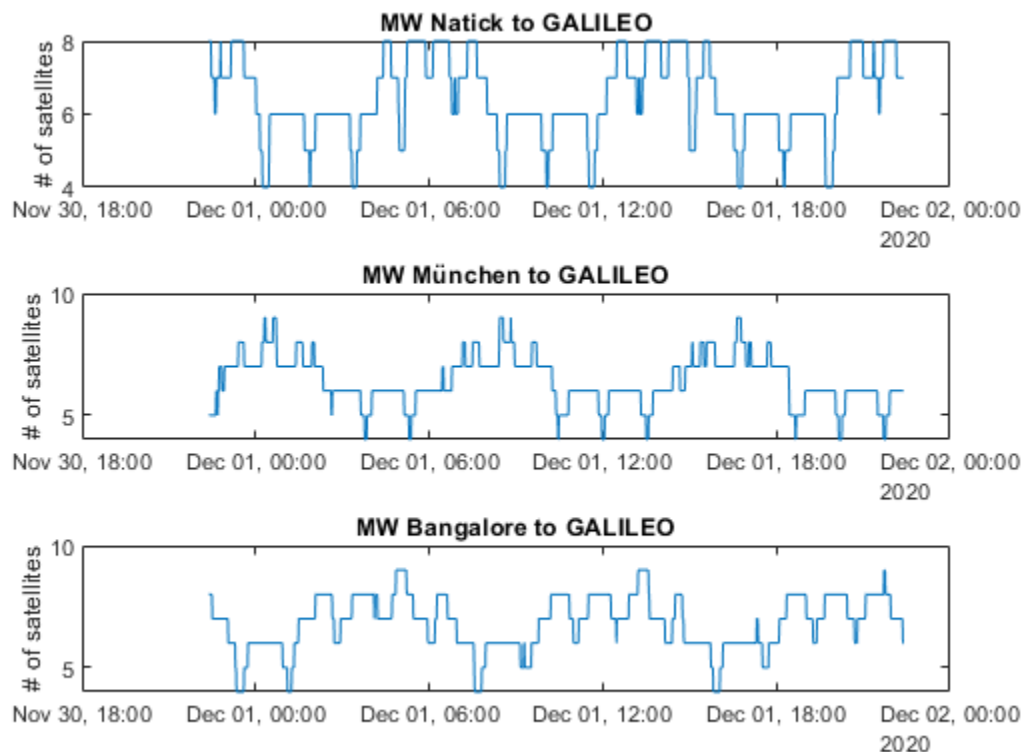
```
% Initialize array with size equal to number of timesteps in scenario
timeSteps = mission.StartDate:seconds(60):mission.StartDate+days(1);
statusUS = zeros(1, numel(timeSteps));
statusDE = statusUS;
statusIN = statusUS;

% Sum cumulative access at each timestep
for idx = 1:24
    statusUS = statusUS + accessStatus(accessUS(idx));
    statusDE = statusDE + accessStatus(accessDE(idx));
    statusIN = statusIN + accessStatus(accessIN(idx));
end
clear idx;
```

```

subplot(3,1,1);
plot(timeSteps, statusUS);
title("MW Natick to GALILEO")
ylabel("# of satellites")
subplot(3,1,2);
plot(timeSteps, statusDE);
title("MW München to GALILEO")
ylabel("# of satellites")
subplot(3,1,3);
plot(timeSteps, statusIN);
title("MW Bangalore to GALILEO")
ylabel("# of satellites")

```



Collect access interval metrics for each ground station in a table for comparison.

```

statusTable = [table(height(intervalsUS), height(intervalsDE), height(intervalsIN)); ...
    table(sum(intervalsUS.Duration)/3600, sum(intervalsDE.Duration)/3600, sum(intervalsIN.Duration)/3600); ...
    table(mean(intervalsUS.Duration/60), mean(intervalsDE.Duration/60), mean(intervalsIN.Duration)/60); ...
    table(mean(statusUS, 2), mean(statusDE, 2), mean(statusIN, 2)); ...
    table(min(statusUS), min(statusDE), min(statusIN)); ...
    table(max(statusUS), max(statusDE), max(statusIN))];
statusTable.Properties.VariableNames = ["MW Natick", "MW München", "MW Bangalore"];
statusTable.Properties.RowNames = ["Total # of intervals", "Total interval time (hrs)", ...
    "Mean interval length (min)", "Mean # of satellites in view", ...
    "Min # of satellites in view", "Max # of satellites in view"];
statusTable

```

statusTable=6x3 table

	MW Natick	MW München	MW Bangalore
Total # of intervals	52	51	45
Total interval time (hrs)	153.92	153.55	162.73
Mean interval length (min)	177.6	180.65	216.98
Mean # of satellites in view	6.4448	6.4289	6.8071
Min # of satellites in view	4	4	4
Max # of satellites in view	8	9	9

Walker-Delta constellations like Galileo are evenly distributed across longitudes. Natick and München are located at similar latitudes, and therefore have very similar access characteristics with respect to the constellation. Bangalore is at a latitude closer to the equator. Despite having a lower number of individual access intervals, it has the highest average number of satellites in view, the highest overall interval time, and the longest average interval duration (by 40 minutes). All locations always have a minimum of 4 satellites in view, as is required for GNSS trilateration.

References

- [1] Wertz, James R, David F. Everett, and Jeffery J. Puschell. *Space Mission Engineering: The New Smad*. Hawthorne, CA: Microcosm Press, 2011. Print.
- [2] The European Space Agency: Galileo Facts and Figures. https://www.esa.int/Applications/Navigation/Galileo/Facts_and_figures

Satellite Constellation Access to a Ground Station

This example demonstrates how to set up access analysis between a ground station and conical sensors onboard a constellation of satellites. A ground station and a conical sensor belonging to a satellite are said to have access to one another if the ground station is inside the conical sensor's field of view and the conical sensor's elevation angle with respect to the ground station is greater than or equal to the latter's minimum elevation angle. The scenario involves a constellation of 40 low-Earth orbit satellites and a geographical site, located at MathWorks Natick. Each satellite has a camera with a field of view of 90 degrees. The entire constellation of satellites is tasked with photographing MathWorks Natick, which is located at 42.3001 degrees North and 71.3504 degrees West. The photographs are required to be taken between 12 May 2020 1:00 PM UTC and 12 May 2020 7:00 PM UTC when MathWorks Natick is adequately illuminated by the sun. In order to capture good quality pictures with minimal atmospheric distortion, the satellite's elevation angle with respect to MathWorks Natick should be at least 30 degrees (please note that 30 degrees was arbitrarily chosen for illustrative purposes). During the 6 hour interval, it is required to determine the times during which each satellite can photograph MathWorks Natick. It is also required to determine the percentage of time during this interval when at least one satellite's camera can see MathWorks Natick. This percentage quantity is termed the system-wide access percentage.

Create a Satellite Scenario

Create a satellite scenario using `satelliteScenario`. Use `datetime` to set the start time to 12-May-2020 1:00:00 PM UTC, and the stop time to 12-May-2020 7:00:00 PM UTC. Set the simulation sample time to 30 seconds.

```
startTime = datetime(2020,5,12,13,0,0);
stopTime = startTime + hours(6);
sampleTime = 30; % seconds
sc = satelliteScenario(startTime,stopTime,sampleTime)

sc =
    satelliteScenario with properties:
        StartTime: 12-May-2020 13:00:00
        StopTime: 12-May-2020 19:00:00
        SampleTime: 30
        Viewers: [0x0 matlabshared.satellitescenario.Viewer]
        Satellites: []
        GroundStations: []
        AutoShow: 1
```

Add Satellites to the Satellite Scenario

Use `satellite` to add satellites to the scenario from the TLE file `leoSatelliteConstellation.tle`. The TLE file defines the mean orbital parameters of 40 generic satellites in nearly circular low-Earth orbits at an altitude and inclination of approximately 500 km and 55 degrees respectively.

```
tleFile = "leoSatelliteConstellation.tle";
sat = satellite(sc,tleFile)

sat =
    1x40 Satellite array with properties:
        Name
```

```

ID
ConicalSensors
Gimbals
Transmitters
Receivers
Accesses
GroundTrack
Orbit
OrbitPropagator
MarkerColor
MarkerSize
ShowLabel
LabelFontColor
LabelFontSize

```

Add Cameras to the Satellites

Use `conicalSensor` to add a conical sensor to each satellite. These conical sensors represent the cameras. Specify their `MaxViewAngle` to be 90 degrees, which defines the field of view.

```

for idx = 1:numel(sat)
    name = sat(idx).Name + " Camera";
    conicalSensor(sat(idx),"Name",name,"MaxViewAngle",90);
end

```

```

% Retrieve the cameras
cam = [sat.ConicalSensors]

```

```

cam =
    1x40 ConicalSensor array with properties:

```

```

    Name
    ID
    MountingLocation
    MountingAngles
    MaxViewAngle
    Accesses
    FieldOfView

```

Define MathWorks Natick Geographical Site in the Satellite Scenario

Use `groundStation` to add a ground station, which represents MathWorks Natick. Specify its `MinElevationAngle` to be 30 degrees. If latitude and longitude are not specified, they default to the coordinates of MathWorks Natick.

```

name = "MathWorks Natick";
minElevationAngle = 30; % degrees
mwNatick = groundStation(sc, ...
    "Name",name, ...
    "MinElevationAngle",minElevationAngle)

```

```

mwNatick =
    GroundStation with properties:

```

```

        Name: "MathWorks Natick"
        ID: 81

```

```
Latitude: 42.3001
Longitude: -71.3504
Altitude: 0
MinElevationAngle: 30
ConicalSensors: []
Gimbals: []
Transmitters: []
Receivers: []
Accesses: []
MarkerColor: [0 1 1]
MarkerSize: 10
ShowLabel: 1
LabelFontColor: [0 1 1]
LabelFontSize: 15
```

Add Access Analysis Between the Cameras and MathWorks Natick

Use `access` to add access analysis between each camera and MathWorks Natick. The access analyses will be used to determine when each camera can photograph MathWorks Natick.

```
for idx = 1:numel(cam)
    access(cam(idx),mwNatick);
end

% Retrieve the access analysis objects
ac = [cam.Accesses];

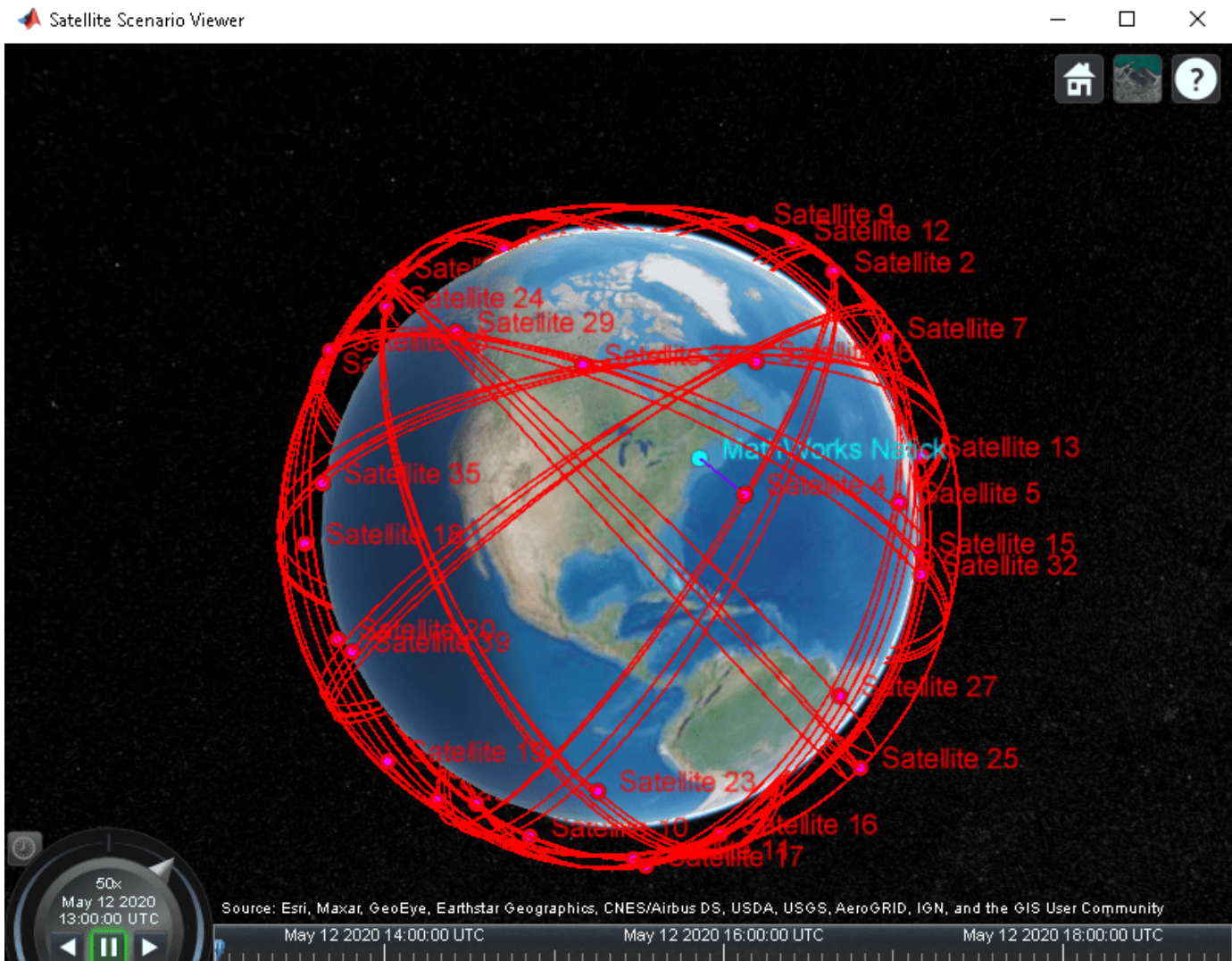
% Properties of access analysis objects
ac(1)

ans =
    Access with properties:
        Sequence: [41 81]
        LineWidth: 1
        LineColor: [0.5000 0 1]
```

Visualize the Scenario

Use `satelliteScenarioViewer` to launch a satellite scenario viewer and visualize the scenario.

```
v = satelliteScenarioViewer(sc);
```

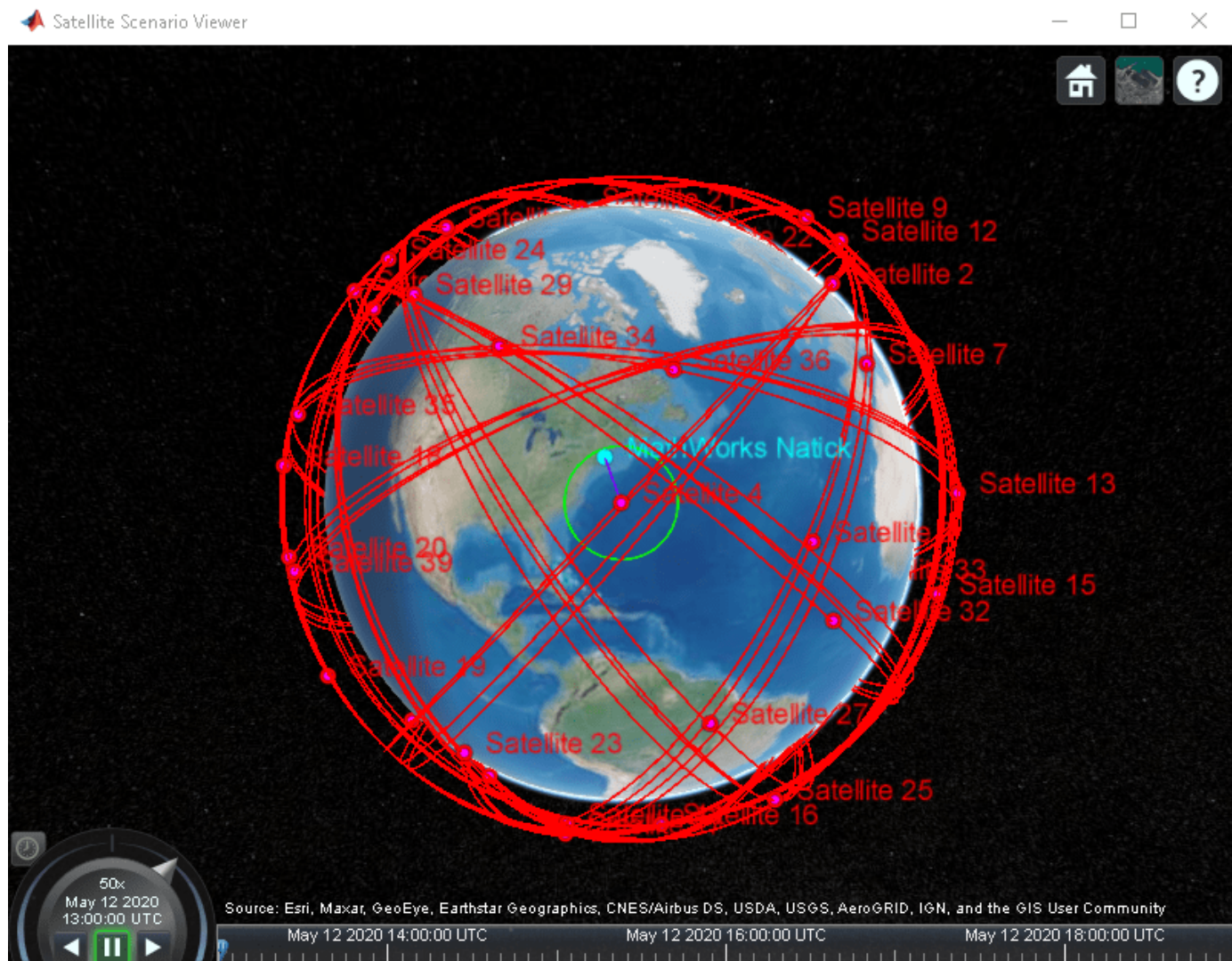
The viewer may be used as a visual confirmation that the scenario has been set up correctly. The violet line indicates that the camera on Satellite 4 and MathWorks Natick have access to one another. This means that MathWorks Natick is inside the camera's field of view and the camera's elevation angle with respect to MathWorks Natick is greater than or equal to 30 degrees. For the purposes of this scenario, this means that the camera can successfully photograph MathWorks Natick.

Visualize the Field Of View of the Camera

Use `fieldOfView` to visualize the field of view of each camera on Satellite 4.

```
fov = fieldOfView(cam([cam.Name] == "Satellite 4 Camera"))

fov =
  FieldOfView with properties:
    LineWidth: 1
    LineColor: [0 1 0]
    VisibilityMode: 'inherit'
```

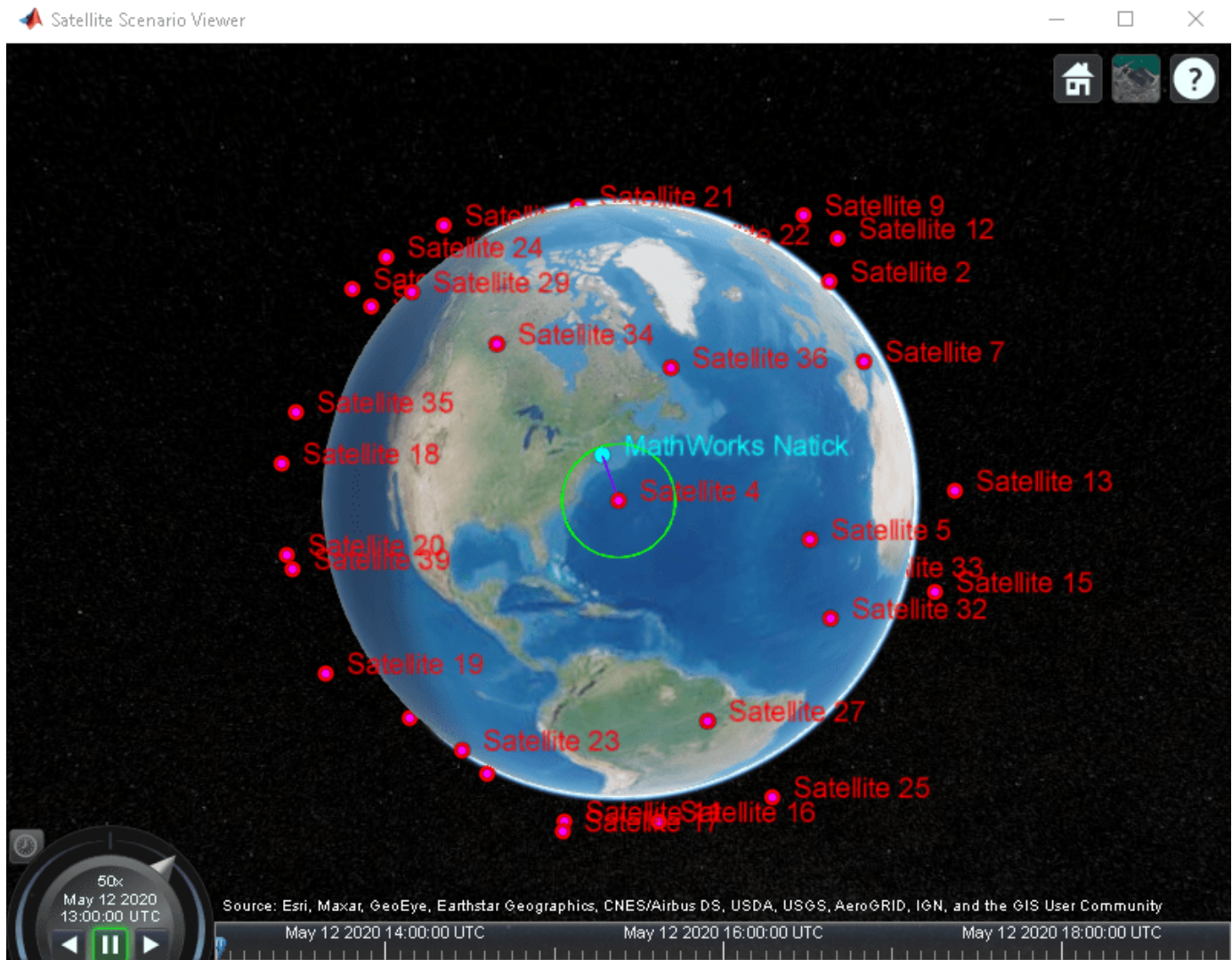


The presence of MathWorks Natick inside the contour is a visual confirmation that it is inside the field of view of the camera onboard Satellite 4.

Customize the Visualizations

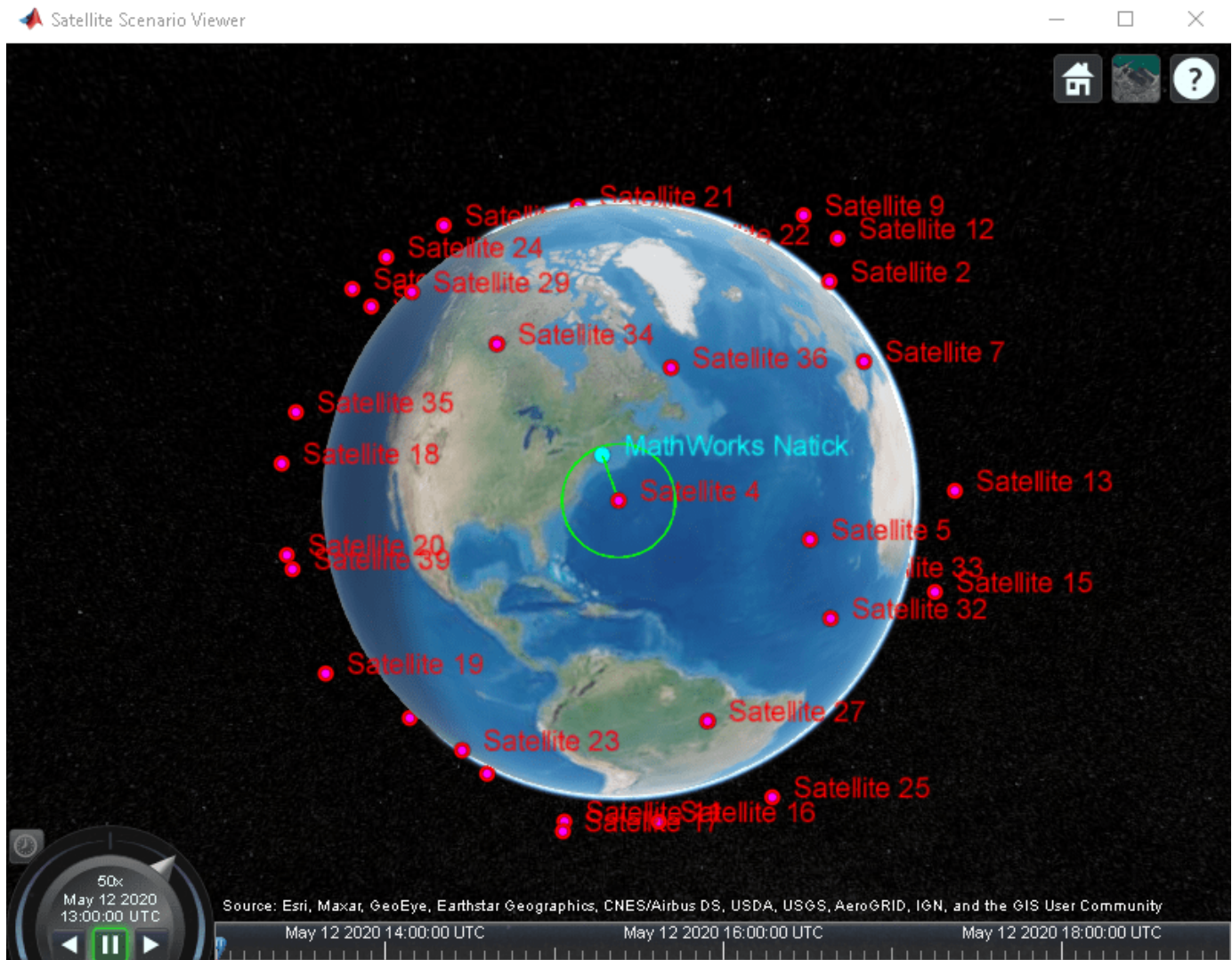
Use `hide` to hide the satellite orbits and declutter the visualization.

```
hide([sat.Orbit]);
```

Change the color of access visualizations to green.

```
for idx = 1:numel(ac)
    ac(idx).LineColor = 'green';
end
```



Determine the Times when the Cameras can Photograph MathWorks Natick

Use `accessIntervals` to determine the times when there is access between each camera and MathWorks Natick. These are the times when the camera can photograph MathWorks Natick

`accessIntervals(ac)`

`ans=30x8 table`

Source	Target	IntervalNumber	StartTime	
"Satellite 1 Camera"	"MathWorks Natick"	1	12-May-2020 13:36:00	12-M
"Satellite 1 Camera"	"MathWorks Natick"	2	12-May-2020 15:23:00	12-M
"Satellite 2 Camera"	"MathWorks Natick"	1	12-May-2020 14:30:30	12-M
"Satellite 3 Camera"	"MathWorks Natick"	1	12-May-2020 13:28:30	12-M
"Satellite 4 Camera"	"MathWorks Natick"	1	12-May-2020 13:00:00	12-M
"Satellite 4 Camera"	"MathWorks Natick"	2	12-May-2020 14:46:00	12-M
"Satellite 5 Camera"	"MathWorks Natick"	1	12-May-2020 16:28:30	12-M
"Satellite 6 Camera"	"MathWorks Natick"	1	12-May-2020 17:05:30	12-M

"Satellite 7 Camera"	"MathWorks Natick"	1	12-May-2020 16:20:00	12-M
"Satellite 8 Camera"	"MathWorks Natick"	1	12-May-2020 15:18:00	12-M
"Satellite 8 Camera"	"MathWorks Natick"	2	12-May-2020 17:03:30	12-M
"Satellite 9 Camera"	"MathWorks Natick"	1	12-May-2020 17:55:30	12-M
"Satellite 10 Camera"	"MathWorks Natick"	1	12-May-2020 18:44:30	12-M
"Satellite 11 Camera"	"MathWorks Natick"	1	12-May-2020 18:39:30	12-M
"Satellite 12 Camera"	"MathWorks Natick"	1	12-May-2020 17:58:00	12-M
"Satellite 29 Camera"	"MathWorks Natick"	1	12-May-2020 13:09:30	12-M
⋮				

The above table consists of the start and end times of each interval during which a given camera can photograph MathWorks Natick. The duration of each interval is reported in seconds. StartOrbit and EndOrbit are the orbit counts of the satellite that the camera is attached to when the access begins and ends. The count starts from the scenario start time.

Use `play` to visualize the simulation of the scenario from its start time to stop time. It can be seen that the green lines appear whenever the camera can photograph MathWorks Natick

```
play(sc);
```




Calculate System-Wide Access Percentage

In addition to determining the times when each camera can photograph MathWorks Natick, it is also required to determine the system-wide access percentage, which is the percentage of time from the scenario start time to stop time when at least one satellite can photograph MathWorks Natick. This is computed as follows:

- For each camera, calculate the access status history to MathWorks Natick using `accessStatus`. For a given camera, this is a row vector of logicals, where each element in the vector represents the access status corresponding to a given time sample. A value of True indicates that the camera can photograph MathWorks Natick at that specific time sample.
- Perform a logical OR on all these row vectors corresponding to access of each camera to MathWorks Natick. This will result in a single row vector of logicals, in which a given element is true if at least one camera can photograph MathWorks Natick at the corresponding time sample for a duration of one scenario sample time of 30 seconds.

- Count the number of elements in the vector whose value is True. Multiply this quantity by the sample time of 30 seconds to determine the total time in seconds when at least one camera can photograph MathWorks Natick.
- Divide this quantity by the scenario duration of 6 hours and multiply by 100 to get the system-wide access percentage.

```

for idx = 1:numel(ac)
    [s,time] = accessStatus(ac(idx));

    if idx == 1
        % Initialize system-wide access status vector in the first iteration
        systemWideAccessStatus = s;
    else
        % Update system-wide access status vector by performing a logical OR
        % with access status for the current camera-MathWorks Natick access
        % analysis
        systemWideAccessStatus = or(systemWideAccessStatus,s);
    end
end
end

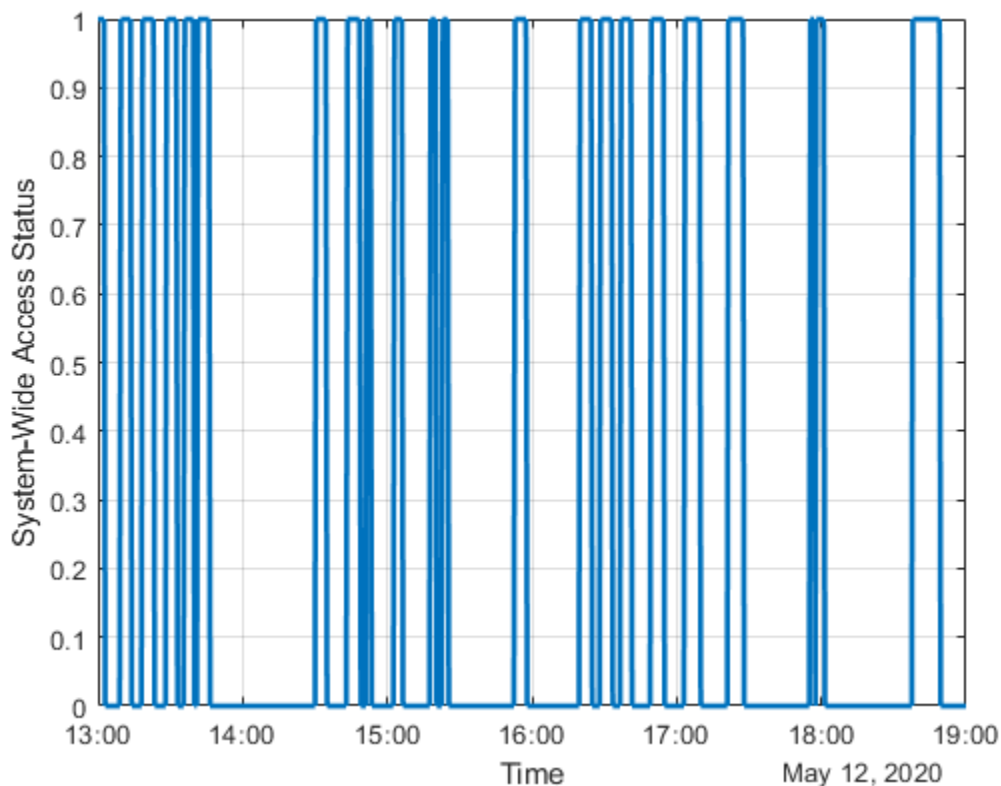
```

Use `plot` to plot the system-wide access status with respect to time.

```

plot(time,systemWideAccessStatus,"LineWidth",2);
grid on;
xlabel("Time");
ylabel("System-Wide Access Status");

```



Whenever system-wide access status is 1 (True), at least one camera can photograph MathWorks Natick.

Use `nnz` to determine the number of elements in `systemWideAccessStatus` whose value is True.

```
n = nnz(systemWideAccessStatus)
n = 203
```

Determine the total time when at least one camera can photograph MathWorks Natick. This is accomplished by multiplying the number of True elements by the scenario's sample time.

```
systemWideAccessDuration = n*sc.SampleTime % seconds
systemWideAccessDuration = 6090
```

Use `seconds` to calculate the total scenario duration.

```
scenarioDuration = seconds(sc.StopTime - sc.StartTime)
scenarioDuration = 21600
```

Calculate the system-wide access percentage.

```
systemWideAccessPercentage = (systemWideAccessDuration/scenarioDuration)*100
systemWideAccessPercentage = 28.1944
```

Improve the System-Wide Access Percentage by Making the Cameras Track MathWorks Natick

The default attitude configuration of the satellites is such that their yaw axes point straight down towards nadir (the point on Earth directly below the satellite). Since the cameras are aligned with the yaw axis by default, they point straight down as well. As a result, MathWorks Natick goes outside the field of view of the cameras before their elevation angle dips below 30 degrees. Therefore, the system-wide access percentage is limited by the field of view of the cameras.

If instead the cameras always point at MathWorks Natick, the latter is always inside the cameras' field of view as long as the Earth is not blocking the line of sight. Consequently, the system-wide access percentage will now be limited by MathWorks Natick's `MinElevationAngle` as opposed to the cameras' field of view. In the former case, the access intervals began and ended when MathWorks Natick entered and left the camera's field of view. It entered the field of view some time after the camera's elevation angle went above 30 degrees, and left the field of view before its elevation angle dipped below 30 degrees. However, if the cameras constantly point at MathWorks Natick, the access intervals will begin when the elevation angle rises above 30 degrees and end when it dips below 30 degrees, thereby increasing the duration of the intervals. Therefore, the system-wide access percentage will increase as well.

Since the cameras are rigidly attached to the satellites, each satellite is required to be continuously reoriented along its orbit so that its yaw axis tracks MathWorks Natick. As the cameras are aligned with the yaw axis, they too will point at MathWorks Natick. Use `pointAt` to make each satellite's yaw axis track MathWorks Natick.

```
for idx = 1:numel(sat)
    pointAt(sat(idx),mwNatick);
end
```

Re-calculate the system-wide access percentage.


```
% Calculate system-wide access status
for idx = 1:numel(ac)
    [s,time] = accessStatus(ac(idx));

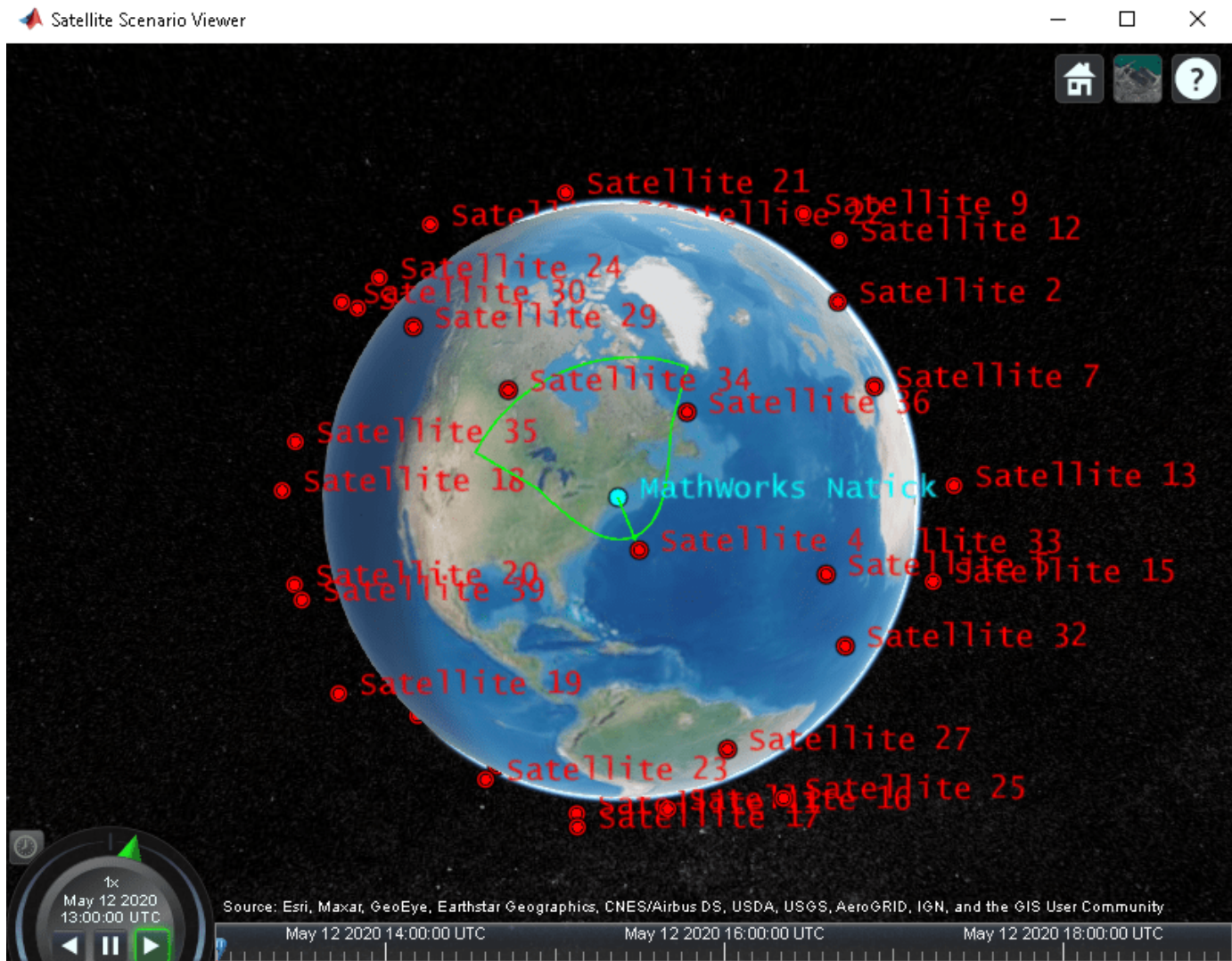
    if idx == 1
        % Initialize system-wide access status vector in the first iteration
        systemWideAccessStatus = s;
    else
        % Update system-wide access status vector by performing a logical OR
        % with access status for the current camera-MathWorks Natick
        % combination
        systemWideAccessStatus = or(systemWideAccessStatus,s);
    end
end

% Calculate system-wide access percentage
n = nnz(systemWideAccessStatus);
systemWideAccessDuration = n*sc.SampleTime;
systemWideAccessPercentageWithTracking = (systemWideAccessDuration/scenarioDuration)*100

systemWideAccessPercentageWithTracking = 38.3333
```

The system-wide access percentage has improved by about 35%. This is the result of the cameras continuously pointing at MathWorks Natick. This can be visualized by using `play` again.

```
play(sc)
```



The field of view contour is no longer circular because the camera is not pointing straight down anymore as it is tracking MathWorks Natick.

Exploring the Example

This example demonstrated how to determine the times at which cameras onboard satellites in a constellation can photograph a geographical site (MathWorks Natick). The cameras were modeled using conical sensors and access analysis was used to calculate the times. Additionally, system-wide access percentage was computed to determine the percentage of time during a 6 hour period when at least one satellite can photograph MathWorks Natick. It was seen that these results depended on which direction the cameras were pointing.

These results are also a function of:

- Orbit of the satellites
- MinElevationAngle of MathWorks Natick
- Mounting position and location of the cameras with respect to the satellites

- Field of view (`MaxViewAngle`) of the cameras if they are not continuously pointing at MathWorks Natick

Modify the above parameters to your requirements and observe their influence on the access intervals and system-wide access percentage. The orbit of the satellites can be changed by explicitly specifying their Keplerian orbital elements using `satellite`. Additionally, the cameras can be mounted on `gimbals`, which can be rotated independent of the satellite. This way, the satellites can point straight down (the default behavior), while the gimbals can be configured so that the cameras independently track MathWorks Natick.

Comparison of Orbit Propagators

This example compares the orbits predicted by the Two-Body-Keplerian, Simplified General Perturbations-4 (SGP4) and Simplified Deep-Space Perturbations-4 (SDP4) orbit propagators. An orbit propagator is a solver that calculates the position and velocity of an object whose motion is predominantly influenced by gravity from celestial bodies. The Two-Body-Keplerian orbit propagator is based on the relative two-body model that assumes a spherical gravity field for the Earth and neglects third body effects and other environmental perturbations, and hence, is the least accurate. The SGP4 orbit propagator accounts for secular and periodic orbital perturbations caused by Earth's geometry and atmospheric drag, and is applicable to near-Earth satellites whose orbital period is less than 225 minutes. The SDP4 orbit propagator builds upon SGP4 by accounting for solar and lunar gravity, and is applicable to satellites whose orbital period is greater than or equal to 225 minutes. The default orbit propagator for `satelliteScenario` is SGP4 for satellites whose orbital period is less than 225 minutes, and SDP4 otherwise.

Create a Satellite Scenario

Create a satellite scenario by using the `satelliteScenario` function. Set the start time to 11-May-2020 12:35:38 PM UTC, and the stop time to 13-May-2020 12:35:38 PM UTC, by using the `datetime` function. Set the sample time to 60 seconds.

```
startTime = datetime(2020,5,11,12,35,38);
stopTime = startTime + days(2);
sampleTime = 60;
sc = satelliteScenario(startTime,stopTime,sampleTime)

sc =
    satelliteScenario with properties:
        StartTime: 11-May-2020 12:35:38
        StopTime: 13-May-2020 12:35:38
        SampleTime: 60
        Viewers: [0x0 matlabshared.satellitescenario.Viewer]
        Satellites: []
        GroundStations: []
        AutoShow: 1
```

Add Satellites to the Satellite Scenario

Add three satellites to the satellite scenario from the two-line element (TLE) file `eccentricOrbitSatellite.tle` by using the `satellite` function. TLE is a data format used for encoding the orbital elements of an Earth-orbiting object defined at a specific time. Assign a Two-Body-Keplerian orbit propagator to the first satellite, SGP4 to the second satellite, and SDP4 to the third satellite.

```
tleFile = "eccentricOrbitSatellite.tle";
satTwoBodyKeplerian = satellite(sc,tleFile, ...
    "Name","satTwoBodyKeplerian", ...
    "OrbitPropagator","two-body-keplerian")

satTwoBodyKeplerian =
    Satellite with properties:
        Name: "satTwoBodyKeplerian"
        ID: 1
```

```
ConicalSensors: []
  Gimbals: []
  Transmitters: []
  Receivers: []
  Accesses: []
  GroundTrack: [1x1 matlabshared.satellitescenario.GroundTrack]
  Orbit: [1x1 matlabshared.satellitescenario.Orbit]
OrbitPropagator: "two-body-keplerian"
  MarkerColor: [1 0 0]
  MarkerSize: 10
  ShowLabel: 1
LabelFontColor: [1 0 0]
LabelFontSize: 15

satSGP4 = satellite(sc,tleFile, ...
  "Name","satSGP4", ...
  "OrbitPropagator","sgp4")

satSGP4 =
  Satellite with properties:
      Name: "satSGP4"
      ID: 2
  ConicalSensors: []
    Gimbals: []
  Transmitters: []
  Receivers: []
  Accesses: []
  GroundTrack: [1x1 matlabshared.satellitescenario.GroundTrack]
  Orbit: [1x1 matlabshared.satellitescenario.Orbit]
OrbitPropagator: "sgp4"
  MarkerColor: [1 0 0]
  MarkerSize: 10
  ShowLabel: 1
LabelFontColor: [1 0 0]
LabelFontSize: 15

satSDP4 = satellite(sc,tleFile, ...
  "Name","satSDP4", ...
  "OrbitPropagator","sdp4")
```

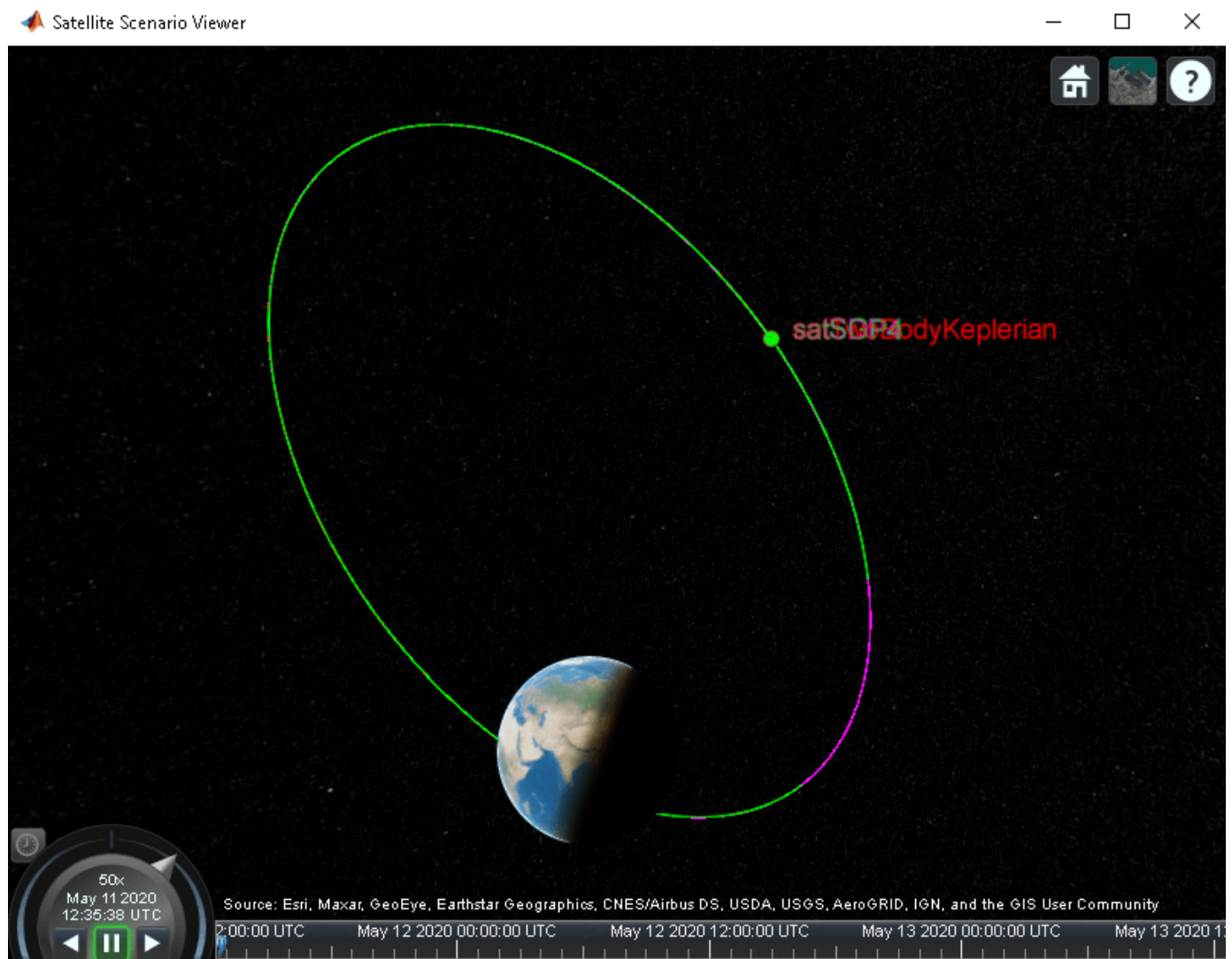
```
satSDP4 =
  Satellite with properties:
      Name: "satSDP4"
      ID: 3
  ConicalSensors: []
    Gimbals: []
  Transmitters: []
  Receivers: []
  Accesses: []
  GroundTrack: [1x1 matlabshared.satellitescenario.GroundTrack]
  Orbit: [1x1 matlabshared.satellitescenario.Orbit]
OrbitPropagator: "sdp4"
  MarkerColor: [1 0 0]
  MarkerSize: 10
  ShowLabel: 1
```

```
LabelFontColor: [1 0 0]
LabelFontSize: 15
```

Visualize the Satellites and their Orbits

Launch a satellite scenario viewer and visualize the satellite scenario by using the `satelliteScenarioViewer` function. Set the visualizations of `satTwoBodyKeplerian` to red, `satSGP4` to green, and `satSDP4` to magenta.

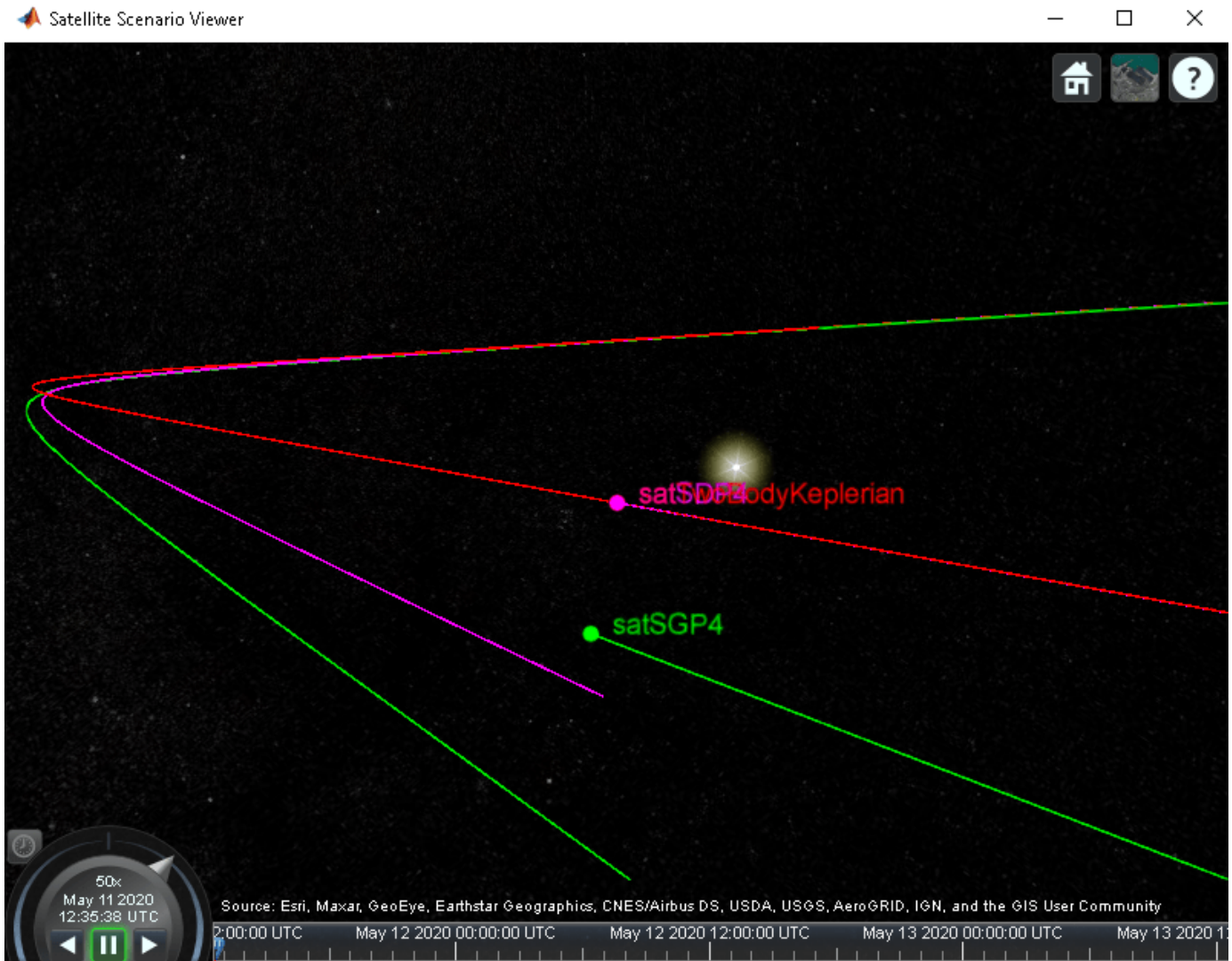
```
v = satelliteScenarioViewer(sc);
satSGP4.MarkerColor = [0 1 0];
satSGP4.Orbit.LineColor = [0 1 0];
satSGP4.LabelFontColor = [0 1 0];
satSDP4.MarkerColor = [1 0 1];
satSDP4.Orbit.LineColor = [1 0 1];
satSDP4.LabelFontColor = [1 0 1];
```



Focus the camera on `satTwoBodyKeplerian` by using the `camtarget` function.


```
camtarget(v, satTwoBodyKeplerian);
```

Left-click anywhere inside the satellite scenario viewer window and move the mouse while holding the click to pan the camera. Adjust the zoom level using the scroll wheel to bring all three satellites into view.



Visualize a Dynamic Animation of the Satellite Movement

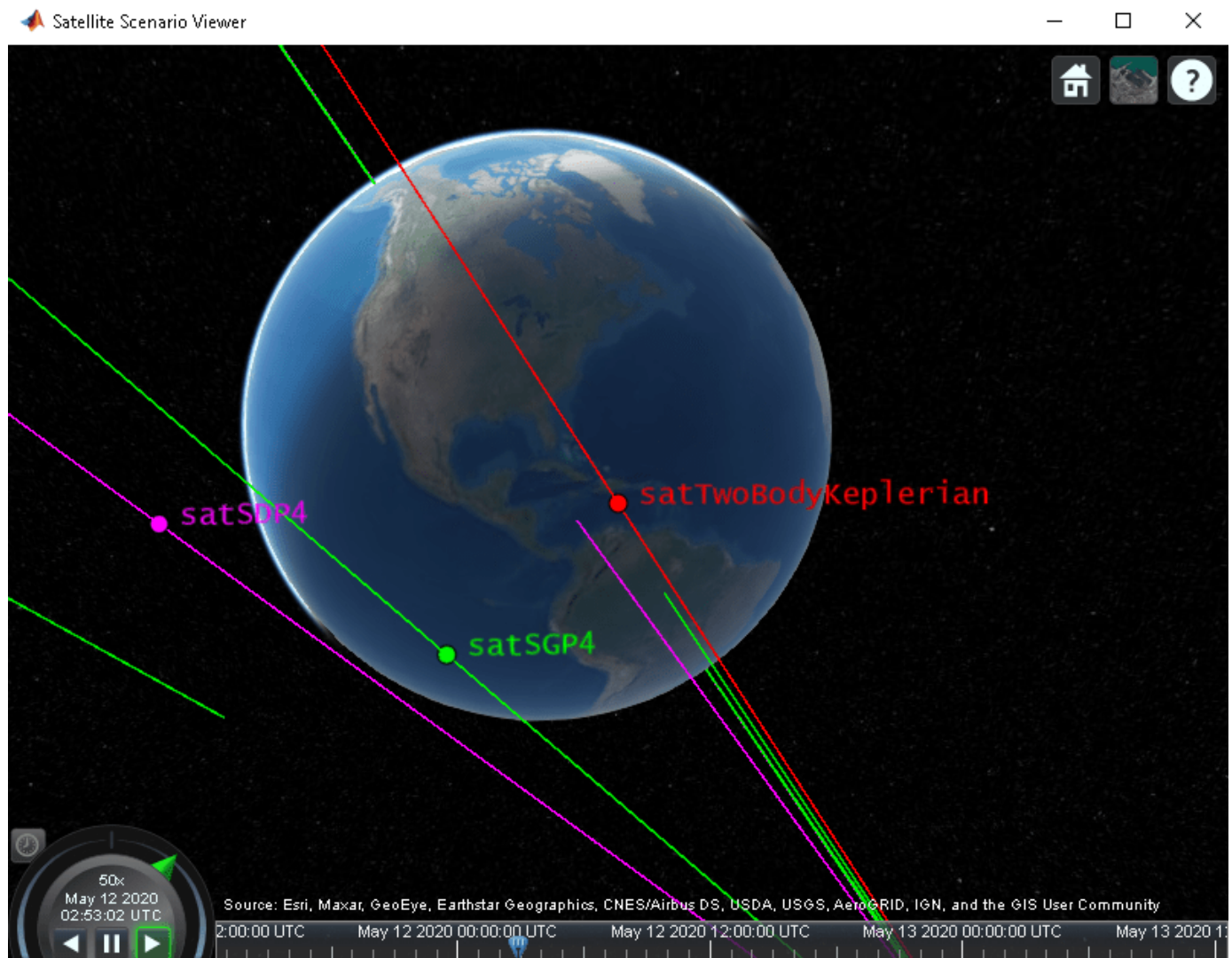
Visualize the movement of the satellites by using the `play` function on the satellite scenario. The `play` function simulates the satellite scenario from the specified `StartTime` to `StopTime` using a step size specified by `SampleTime`, and plays the results on the satellite scenario viewer.

```
play(sc)
```

Use the playback controls located at the bottom of the satellite scenario viewer window to control the playback speed and direction. Focus the camera again on `satTwoBodyKeplerian` by using the `camtarget` function, and bring all three satellites into view by adjusting the zoom level.

```
camtarget(v, satTwoBodyKeplerian);
```

The positions of the three satellites diverge over time.



Obtain the Position and Velocity History of the Satellites

Return the position and velocity history of the satellites in the Geocentric Celestial Reference Frame (GCRF) by using the `states` function.

```
[positionTwoBodyKeplerian,velocityTwoBodyKeplerian,time] = states(satTwoBodyKeplerian);
[positionSGP4,velocitySGP4] = states(satSGP4);
[positionSDP4,velocitySDP4] = states(satSDP4);
```

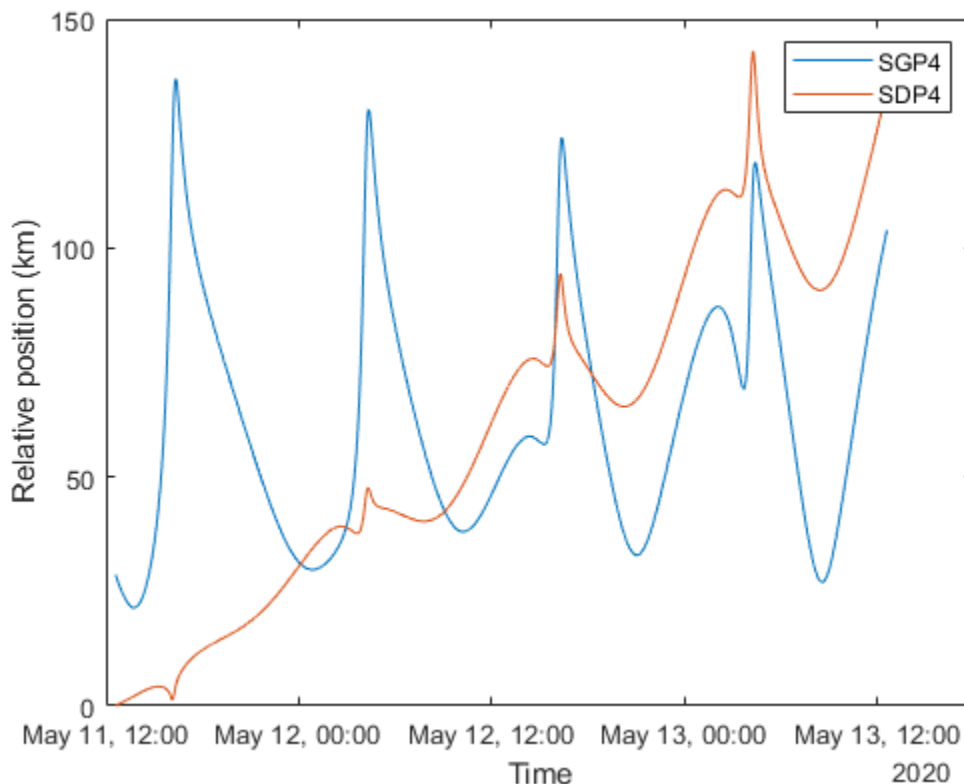
Plot Magnitude of Relative Position with Respect to Two-Body-Keplerian Prediction

Calculate the magnitude of the relative position of `satSGP4` and `satSDP4` with respect to `satTwoBodyKeplerian` by using the `vecnorm` function.

```
sgp4RelativePosition = vecnorm(positionSGP4 - positionTwoBodyKeplerian,2,1);
sdp4RelativePosition = vecnorm(positionSDP4 - positionTwoBodyKeplerian,2,1);
```


Plot the magnitude of the relative positions in kilometers of satSGP4 and satSDP4 with respect to that of satTwoBodyKeplerian by using the plot function.

```
sgp4RelativePositionKm = sgp4RelativePosition/1000;
sdp4RelativePositionKm = sdp4RelativePosition/1000;
plot(time,sgp4RelativePositionKm,time,sdp4RelativePositionKm)
xlabel("Time")
ylabel("Relative position (km)")
legend("SGP4","SDP4")
```



The initial relative position of satSGP4 is non-zero and that of satSDP4 is zero because the initial positions of satTwoBodyKeplerian and satSDP4 are calculated from the TLE file using the SDP4 orbit propagator, while the initial position of satSGP4 is calculated using the SGP4 orbit propagator. Over time, the position of satSDP4 deviates from that of satTwoBodyKeplerian because the subsequent positions of the former are calculated using the SDP4 orbit propagator, while those of the latter are calculated using the Two-Body-Keplerian orbit propagator. The SDP4 orbit propagator provides higher precision because unlike the Two-Body-Keplerian orbit propagator, it accounts for oblateness of the Earth, atmospheric drag, and gravity from the sun and the moon.

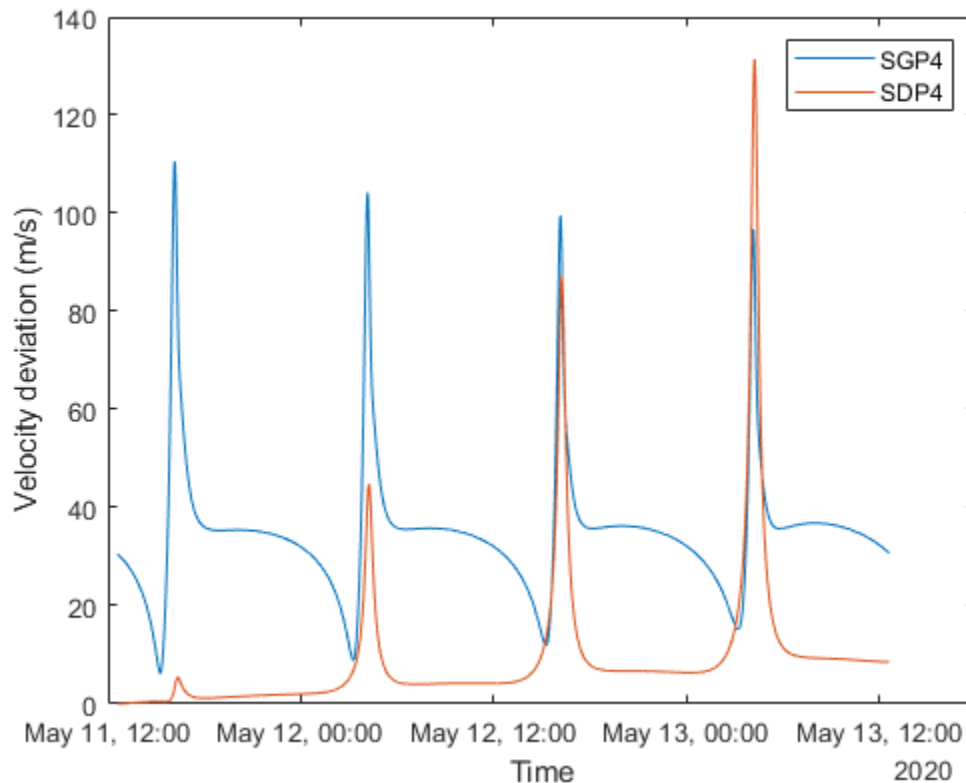
Plot Magnitude of Relative Velocity with Respect to Two-Body-Keplerian Prediction

Calculate the magnitude of the relative velocity of satSGP4 and satSDP4 with respect to satTwoBodyKeplerian by using the vecnorm function.

```
sgp4RelativeVelocity = vecnorm(velocitySGP4 - velocityTwoBodyKeplerian,2,1);
sdp4RelativeVelocity = vecnorm(velocitySDP4 - velocityTwoBodyKeplerian,2,1);
```

Plot the magnitude of the relative velocities in meters per second of `satSGP4` and `satSDP4` with respect to `satTwoBodyKeplerian` by using the `plot` function.

```
plot(time,sgp4RelativeVelocity,time,sdp4RelativeVelocity)
xlabel("Time")
ylabel("Velocity deviation (m/s)")
legend("SGP4","SDP4")
```



The initial relative velocity of `satSDP4` is zero because similar to the initial position, the initial velocity of `satTwoBodyKeplerian` and `satSDP4` are also calculated from the TLE file using the SDP4 orbit propagator. Over time, the velocity of `satSDP4` deviates from that of `satTwoBodyKeplerian` because at all other times, the velocity of `satTwoBodyKeplerian` is calculated using the Two-Body-Keplerian orbit propagator, which has lower precision when compared to that of the SDP4 orbit propagator that is used for calculating the velocity of `satSDP4`. The spikes correspond to the periaapsis (the closest point in the orbit from the center of mass of the Earth), where the magnitudes of the velocity errors are pronounced.

Conclusion

The deviations in the plots are the result of varying levels of accuracy of the three orbit propagators. The Two-Body-Keplerian orbit propagator is the least accurate as it assumes that the gravity field of the Earth is spherical, and also neglects all other sources of orbital perturbations. The SGP4 orbit propagator is more accurate as it accounts for the oblateness of the Earth and atmospheric drag. The SDP4 orbit propagator is the most accurate among the three because it also accounts for solar and

lunar gravity, which is more pronounced in this example because the orbital period is greater than 225 minutes, thereby taking the satellite farther away from the Earth.

Detect and Track LEO Satellite Constellation with Ground Radars

This example shows how to import a Two-Line Element (TLE) file of a satellite constellation, simulate radar detections of the constellation, and track the constellation.

The task of populating and maintaining a catalog of space objects orbiting Earth is crucial in space surveillance. This task consists of several processes: detecting and identifying new objects and adding them to the catalog, updating known objects orbits in the catalog, tracking orbit changes throughout their lifetime, and predicting reentries in the atmosphere. In this example, we are studying how to detect and track new satellites and add them to a catalog.

To guarantee safe operations in space and prevent collisions with other satellites or known debris, it is important to correctly detect and track newly launched satellites. Space agencies typically share prelaunch information, which can be used to select a search strategy. A Low Earth Orbit (LEO) satellite search strategy consisting of fence-type radar systems is commonly used. A fence-type radar system searches a finite volume in space and detects satellites as they pass through its field of view. This strategy can detect and track newly launched constellation quickly. [1]

Importing a satellite constellation from a TLE file

Two-Line Element sets are a common data format to save orbital information of satellites. You can use the `satelliteScenario` object to import satellite orbits defined in a TLE file. By default, the imported satellite orbits are propagated using the SGP4 orbit propagation algorithm which provides good accuracy for LEO objects. In this example, these orbits provide with the ground truth to test the radar tracking system capability to detect newly launched satellites.

```
% Create a satellite scenario
satscene = satelliteScenario;
% Add satellites from TLE file.
tleFile = "leoSatelliteConstellation.tle";
constellation = satellite(satscene, tleFile);
```

Use the satellite scenario viewer to visualize the constellation.

```
play(satscene);
```

Simulating synthetic detections and track constellation

Modeling space surveillance radars

Define two stations with fan-shaped radar beams looking into space. The fans cut through the satellite orbits to maximize the number of detections. The radar stations located on North America form an East-West fence.

```
% First station coordinates in LLA
station1 = [48 -80 0];

% Second station coordinates in LLA
station2 = [50 -117 0];
```

Each station is equipped with a radar, which is modeled by using a `fusionRadarSensor` object. In order to detect satellites in the LEO range, the radar has the following requirements:

- Detecting a 10 dBsm object up to 2000 km away

- Resolving objects horizontally and vertically with a precision of 100 m at 2000 km range
- Having a field of view of 120 degrees in azimuth and 30 degrees in elevation
- Looking up into space

```

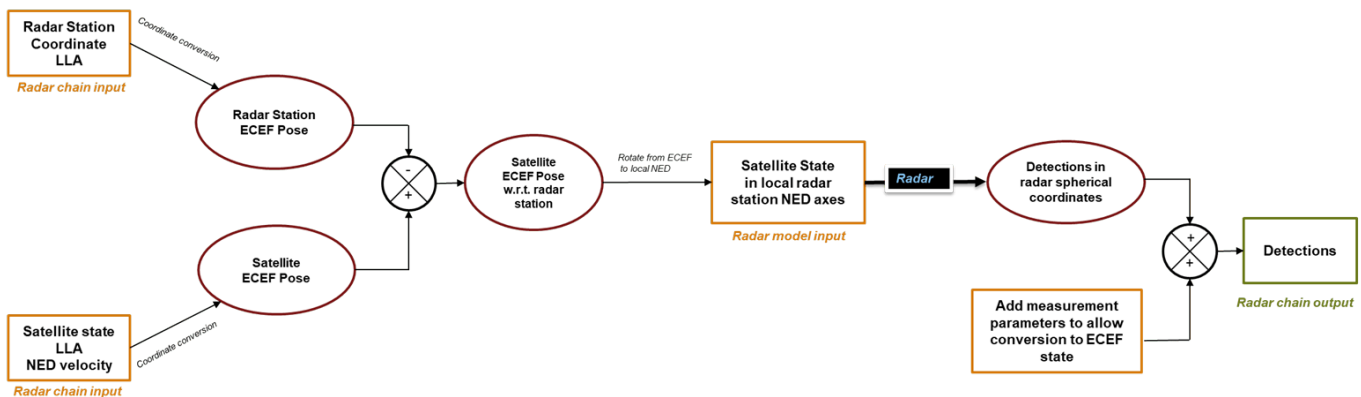
% Create fan-shaped monostatic radars
fov = [120;40];
radar1 = fusionRadarSensor(1,...
    'UpdateRate',0.1,... 10 sec
    'ScanMode','No scanning',...
    'MountingAngles',[0 90 0],... look up
    'FieldOfView',fov,... degrees
    'ReferenceRange',2000e3,... m
    'RangeLimits', [0 2000e3], ... m
    'ReferenceRCS', 10,... dBsm
    'HasFalseAlarms',false,...
    'HasNoise', true,...
    'HasElevation',true,...
    'AzimuthResolution',0.03,... degrees
    'ElevationResolution',0.03,... degrees
    'RangeResolution',2000, ... m % accuracy ~= 2000 * 0.05 (m)
    'DetectionCoordinates','Sensor Spherical',...
    'TargetReportFormat','Detections');
    
```

```

radar2 = clone(radar1);
radar2.SensorIndex = 2;
    
```

Radar Processing Chain

In this example, several coordinate conversions and axes transformation are performed to properly run the radar tracking chain. The diagram below illustrates how the inputs defined above are transformed and passed to the radar.



In the first step, you calculate each satellite pose in the local radar station NED axes. You achieve this by first obtaining the ground station ECEF pose and converting the satellite position and velocity to the ECEF coordinates. The radar input is obtained by taking the differences between the satellite pose and the ground station pose and rotating the differences into ground station local NED axes. See the **assembleRadarInputs** supporting function for the implementation details.

In the second step, you add the required information to the detection object so that the tracker can operate with an ECEF state. You use the **MeasurementParameters** property in each object detection to achieve that purpose, as shown in the **addMeasurementParams** supporting function.

Defining a tracker

The radar models you defined above output detections. To estimate the satellite orbits, you use a tracker. The Sensor Fusion and Tracking Toolbox™ provides a variety of multi-object trackers. In this example, you choose a Joint Probabilistic Data Association (JPDA) tracker because it offers a good balance of tracking performance and computational cost.

You need to define a tracking filter for the tracker. You can use a lower fidelity model than SGP4, such as a Keplerian integration of the equation of motion, to track the satellite. Often, the lack of fidelity in the motion model of targets is compensated by measurement updates and incorporating process noise in the filter. The supporting function **initKeplerUKF** defines the tracking filter.

```
% Define the tracker
tracker = trackerJPDA('FilterInitializationFcn',@initKeplerUKF,...
    'HasDetectableTrackIDsInput',true,...
    'ClutterDensity',1e-40,...
    'AssignmentThreshold',1e4,...
    'DeletionThreshold',[5 8],...
    'ConfirmationThreshold',[5 8]);
```

Running the simulation

In the remainder of this example, you step through the scenario to simulate radar detections and track satellites. This section uses a separate helper class `helperScenarioGlobeViewer` for visualization. You can use this helper class to display sensor and tracking data with uncertainty ellipses and show the true position of each satellite.

```
globeDisplay = helperScenarioGlobeViewer;

% Define coverage configuration of each radar and visualize it on the globe
ned1 = dcmecef2ned(station1(1), station1(2));
ned2 = dcmecef2ned(station2(1), station2(2));
covcon(1) = coverageConfig(radar1,lla2ecef(station1),quaternion(ned1,'rotmat','frame'));
covcon(2) = coverageConfig(radar2,lla2ecef(station2),quaternion(ned2, 'rotmat','frame'));
plotCoverage(globeDisplay, covcon)
```

You first generate the entire history of the states of the constellation over 5 hours. Then, you simulate radar detections and generate tracks in a loop.

```
satscene.StopTime = satscene.StartTime + hours(5);
satscene.SampleTime = 10;
numSteps = ceil(seconds(satscene.StopTime - satscene.StartTime)/satscene.SampleTime);

% Get constellation positions and velocity over the course of the simulation
plats = repmat(...
    struct('PlatformID',0,'Position',[0 0 0], 'Velocity', [0 0 0]),...
    numSteps, 40);
for i=1:numel(constellation)
    [pos, vel] = states(constellation(i),'CoordinateFrame',"Geographic");
    for j=1:numSteps
        plats(j,i).Position = pos(:,j)';
        plats(j,i).Velocity = vel(:,j)';
        plats(j,i).PlatformID = i;
    end
end

% Initialize tracks and tracks log
```

```

confTracks = objectTrack.empty(0,1);
trackLog = cell(1,numSteps);

% Initialize radar plots
radarplt = helperRadarPlot(fov);

% Set random seed for reproducible results
s = rng;
rng(2020);
step = 0;
while step < numSteps
    time = step*satscene.SampleTime;
    step = step + 1;

    % Generate detections of the constellation following the radar
    % processing chain
    targets1 = assembleRadarInputs(station1, plats(step,:));
    [dets1,numdets1] = radar1(targets1, time);
    dets1 = addMeasurementParams(dets1,numdets1,station1);

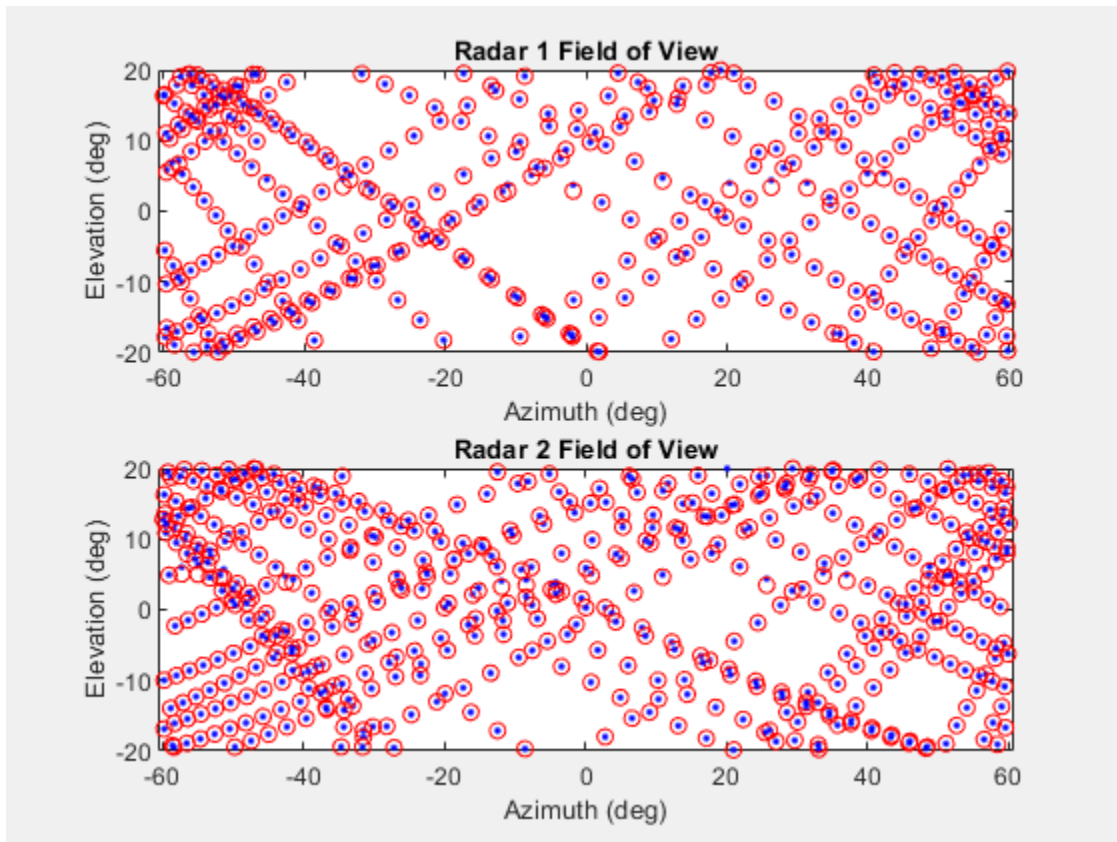
    targets2 = assembleRadarInputs(station2, plats(step,:));
    [dets2, numdets2] = radar2(targets2, time);
    dets2 = addMeasurementParams(dets2, numdets2, station2);

    detections = [dets1; dets2];
    updateRadarPlots(radarplt,targets1, targets2 ,dets1, dets2)

    % Generate and update tracks
    detectableInput = isDetectable(tracker,time, covcon);
    if ~isempty(detections) || isLocked(tracker)
        [confTracks,~,~,info] = tracker(detections,time,detectableInput);
    %     confTracks = deleteBadTracks(tracker,confTracks);
    end
    trackLog{step} = confTracks;

    % Update globe display
    updateDisplay(globeDisplay,time,plats(step,:),detections,[],confTracks);
end

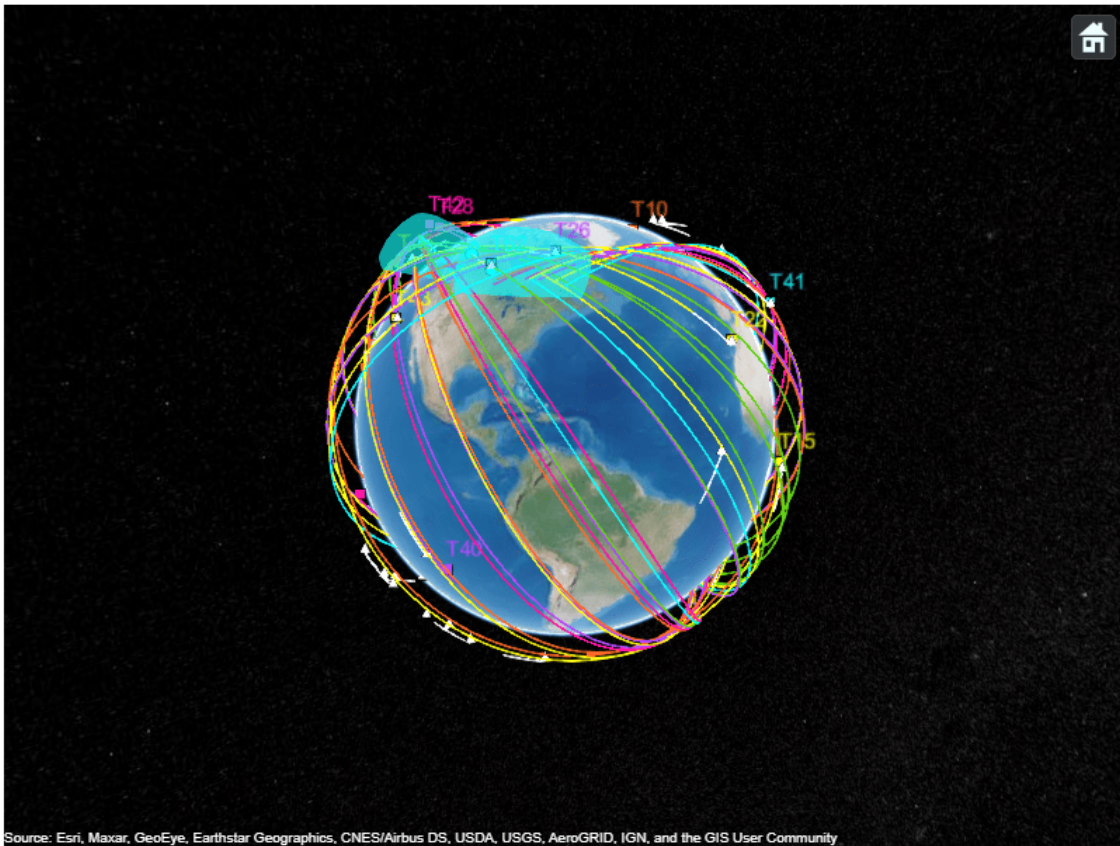
```



The plot above shows the orbits (blue dots) and the detections (red circles) from the point of view of each radar.

```
% Restore previous random seed state  
rng(s);
```

```
figure;  
snap(globeDisplay);
```

After 5 hours of tracking, about half the constellation is tracked successfully. Maintaining tracks with a partial orbit coverage is challenging since satellites can often stay undetected for long periods of time in this configuration. In this example, there are only two radar stations. Additional tracking stations are expected to generate better tracking performance. The assignment metrics, which evaluate the tracking performance by comparing between the true objects and the tracks, are shown below.

```
% Show Assignment metrics
truthIdFcn = @(x)[x.PlatformID];

tam = trackAssignmentMetrics('DistanceFunctionFormat','custom',...
    'AssignmentDistanceFcn',@distanceFcn,...
    'DivergenceDistanceFcn',@distanceFcn,...
    'TruthIdentifierFcn',truthIdFcn,...
    'AssignmentThreshold',1000,...
    'DivergenceThreshold',2000);

for i=1:numSteps
    % Extract the tracker and ground truth at the i-th tracker update
    tracks = trackLog{i};
    truths = plats(i,:);
    % For correct truth-track assignment evaluation, the truth is converted
```

```

% to ECEF
for j=1:numel(truths)
    R = dcmecef2ned(truths(j).Position(1), truths(j).Position(2));
    truths(j).Velocity = truths(j).Velocity * R;
    truths(j).Position = lla2ecef(truths(j).Position);
end
% Extract summary of assignment metrics against tracks and truths
[trackAM,truthAM] = tam(tracks, truths);

end

% Show cumulative metrics for each individual recorded truth object
results = truthMetricsTable(tam);
results(:,{'TruthID', 'AssociatedTrackID', 'BreakLength', 'EstablishmentLength'})

ans=40x4 table
    TruthID    AssociatedTrackID    BreakLength    EstablishmentLength
    _____    _____    _____    _____
         1             57             5             232
         2             46             0            1283
         3             32             0             668
         4             62            12             492
         5             22             0             436
         6             54             5             807
         7             26             0             513
         8             31             0             665
         9             43             0            1221
        10             56             0            1500
        11             49             0            1339
        12             41             0            1056
        13             NaN             0            1800
        14             NaN             0            1800
        15             NaN             0            1800
        16             NaN             0            1800
         :

```

The table above lists 40 satellites in the launched constellation and shows the tracked satellites with associated track IDs. A track ID of value NaN indicates that the satellite is not tracked by the end of the simulation. This either means that the orbit of the satellite did not pass through the field of view of one of the two radars or the track of the satellite has been dropped. The tracker can drop a track due to an insufficient number of initial detections, which leads to a large uncertainty on the estimate. Alternately, the tracker can drop the track if the satellite is not re-detected soon enough, such that the lack of updates leads to divergence and eventually deletion.

Summary

In this example, you have learned how to use the `satelliteScenario` object from the Aerospace Toolbox™ to import orbit information from TLE files. You propagated the satellite trajectories using SGP4 and visualized the scenario using the Satellite Scenario Viewer. You learned how to use the radar and tracker models from the Sensor Fusion and Tracking Toolbox™ to model a space surveillance radar tracking system. The constructed tracking system can predict the estimated orbit of each satellite using a low fidelity model.

Supporting functions

initKeplerUKF initializes an Unscented Kalman filter using the Keplerian motion model.

```
function filter = initKeplerUKF(detection)

radarsphmeas = detection.Measurement;
[x, y, z] = sph2cart(deg2rad(radarsphmeas(1)),deg2rad(radarsphmeas(2)),radarsphmeas(3));
radarcartmeas = [x y z];
Recef2radar = detection.MeasurementParameters.Orientation;
ecefmeas = detection.MeasurementParameters.OriginPosition + radarcartmeas*Recef2radar;
% This is equivalent to:
% Ry90 = [0 0 -1 ; 0 1 0; 1 0 0]; % frame rotation of 90 deg around y axis
% nedmeas(:) = Ry90' * radarcartmeas(:);
% ecefmeas = lla2ecef(lla) + nedmeas * dcmecef2ned(lla(1),lla(2));
initState = [ecefmeas(1); 0; ecefmeas(2); 0; ecefmeas(3); 0];

sigpos = 2;% m
sigvel = 0.5;% m/s^2

filter = trackingUKF(@keplerorbit,@cvmeas,initState,...
    'StateCovariance',diag(repmat([1000, 10000].^2,1,3)),...
    'ProcessNoise',diag(repmat([sigpos, sigvel].^2,1,3)));

end

function state = keplerorbit(state,dt)
% keplerorbit performs numerical integration to predict the state of
% Keplerian bodies. The state is [x;vx;y;vy;z;vz]

% Runge-Kutta 4th order integration method:
k1 = kepler(state);
k2 = kepler(state + dt*k1/2);
k3 = kepler(state + dt*k2/2);
k4 = kepler(state + dt*k3);

state = state + dt*(k1+2*k2+2*k3+k4)/6;

function dstate=kepler(state)
    x =state(1,:);
    vx = state(2,:);
    y=state(3,:);
    vy = state(4,:);
    z=state(5,:);
    vz = state(6,:);

    mu = 398600.4405*1e9; % m^3 s^-2
    omega = 7.292115e-5; % rad/s

    r = norm([x y z]);
    g = mu/r^2;

    % Coordinates are in a non-inertial frame, account for Coriolis
    % and centripetal acceleration
    ax = -g*x/r + 2*omega*vy + omega^2*x;
    ay = -g*y/r - 2*omega*vz + omega^2*y;
    az = -g*z/r;
    dstate = [vx;ax;vy;ay;vz;az];
```

```

    end
end

```

isDetectable is used in the example to determine which tracks are detectable at a given time.

```

function detectInput = isDetectable(tracker,time,covcon)

if ~isLocked(tracker)
    detectInput = zeros(0,1,'uint32');
    return
end
tracks = tracker.predictTracksToTime('all',time);
if isempty(tracks)
    detectInput = zeros(0,1,'uint32');
else
    alltrackid = [tracks.TrackID];
    isDetectable = zeros(numel(tracks),numel(covcon),'logical');
    for i = 1:numel(tracks)
        track = tracks(i);
        pos_scene = track.State([1 3 5]);
        for j=1:numel(covcon)
            config = covcon(j);
            % rotate position to sensor frame:
            d_scene = pos_scene(:) - config.Position(:);
            scene2sens = rotmat(config.Orientation,'frame');
            d_sens = scene2sens*d_scene(:);
            [az,el] = cart2sph(d_sens(1),d_sens(2),d_sens(3));
            if abs(rad2deg(az)) <= config.FieldOfView(1)/2 && abs(rad2deg(el)) < config.FieldOfView(2)
                isDetectable(i,j) = true;
            else
                isDetectable(i,j) = false;
            end
        end
    end
    detectInput = alltrackid(any(isDetectable,2))';
end
end

```

deleteBadTracks is used to remove tracks that obviously diverged. Specifically, diverged tracks in this example are tracks whose current position has fallen on the surface of the earth and tracks whose covariance has become too large.

```

function tracks = deleteBadTracks(tracker,tracks)
% remove divergent tracks:
% - tracks with covariance > 1e10 (100 km standard deviation)
% - tracks with estimated position outside of LEO bounds
n = numel(tracks);
toDelete = zeros(1,n,'logical');
for i=1:numel(tracks)
    [pos, cov] = getTrackPositions(tracks(i),[ 1 0 0 0 0 0 ; 0 0 1 0 0 0; 0 0 0 0 1 0]);
    if norm(pos) < 6500*1e3 || norm(pos) > 8500*1e3 || max(cov,[],'all') > 1e10
        deleteTrack(tracker,tracks(i).TrackID);
        toDelete(i) =true;
    end
end
tracks(toDelete) = [];
end

```

assembleRadarInput is used to construct the constellation poses in each radar body frame. This is the first step described in the diagram.

```
function targets = assembleRadarInputs(station, constellation)
% For each satellite in the constellation, derive its pose with respect to
% the radar frame.
% inputs:
%     - station      : LLA vector of the radar ground station
%     - constellation : Array of structs containing the LLA position
%                       and NED velocity of each satellite
% outputs:
%     - targets      : Array of structs containing the pose of each
%                       satellite with respect to the radar, expressed in the local
%                       ground radar frame (NED)

% Template structure for the outputs which contains all the field required
% by the radar step method
targetTemplate = struct( ...
    'PlatformID', 0, ...
    'ClassID', 0, ...
    'Position', zeros(1,3), ...
    'Velocity', zeros(1,3), ...
    'Acceleration', zeros(1,3), ...
    'Orientation', quaternion(1,0,0,0), ...
    'AngularVelocity', zeros(1,3),...
    'Dimensions', struct( ...
        'Length', 0, ...
        'Width', 0, ...
        'Height', 0, ...
        'OriginOffset', [0 0 0]), ...
    'Signatures', {{rcsSignature}});

% First convert the current satellite pose to ECEF
targetPoses = repmat(targetTemplate, 1, numel(constellation));
for i=1:numel(constellation)
    lla = constellation(i).Position;
    targetPoses(i).Position = lla2ecef(lla);
    vned = constellation(i).Velocity;
    Rned2ecef = dcmecef2ned(lla(1),lla(2));
    targetPoses(i).Velocity(:) = Rned2ecef*vned(:);
    targetPoses(i).PlatformID = constellation(i).PlatformID;
    % Orientation and angular velocity are left null, assuming satellite to
    % be point targets with a uniform rcs
end

% Then derive the radar pose in ECEF based on the ground station location
Recef2station = dcmecef2ned(station(1), station(2));
radarPose.Orientation = quaternion(Recef2station,'rotmat','frame');
radarPose.Position = lla2ecef(station);
radarPose.Velocity = zeros(1,3);
radarPose.AngularVelocity = zeros(1,3);

% Finally, take the difference and rotate each vector to the ground station
% NED axes
targets = targetPoses;
for i=1: numel(targetPoses)
    thisTgt = targetPoses(i);
```

```

pos = Recef2station*(thisTgt.Position(:) - radarPose.Position(:));
vel = Recef2station*(thisTgt.Velocity(:) - radarPose.Velocity(:)) - cross(radarPose.AngularV
angVel = thisTgt.AngularVelocity(:) - radarPose.AngularVelocity(:);
orient = radarPose.Orientation' * thisTgt.Orientation;

% Store into target structure array
targets(i).Position(:) = pos;
targets(i).Velocity(:) = vel;
targets(i).AngularVelocity(:) = angVel;
targets(i).Orientation = orient;
end
end

```

addMeasurementParam implements step 2 in the radar chain process as described in the diagram.

```

function dets = addMeasurementParams(dets, numdets, station)
% Add radar station information to the measurement parameters
Recef2station = dcmecef2ned(station(1), station(2));
for i=1:numdets
    dets{i}.MeasurementParameters.OriginPosition = lla2ecef(station);
    dets{i}.MeasurementParameters.IsParentToChild = true; % parent = ecef, child = radar
    dets{i}.MeasurementParameters.Orientation = dets{i}.MeasurementParameters.Orientation' * Recef2station;
end
end

```

distanceFcn is used with the assignment metrics to evaluate the tracking assignment.

```

function d = distanceFcn(track, truth)

estimate = track.State([1 3 5 2 4 6]);
true = [truth.Position(:) ; truth.Velocity(:)];
cov = track.StateCovariance([1 3 5 2 4 6], [1 3 5 2 4 6]);
d = (estimate - true)' / cov * (estimate - true);
end

```

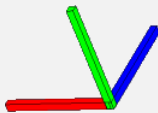
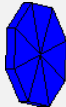

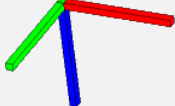
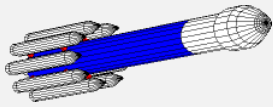





Reference

[1] Sridharan, Ramaswamy, and Antonio F. Pensa, eds. *Perspectives in Space Surveillance*. MIT Press, 2017.

AC3D Files and Thumbnails

AC3D Files and Thumbnails Overview

Aerospace Toolbox demos use the following AC3D files, located in the *matlabroot\toolbox\ aero \astdemos* folder. For other AC3D files, see <https://www.flightgear.org/download/download-aircraft/> and click the **Download Aircraft** link.

Thumbnail	AC3D File
	ac3d_xyzisrgb.ac
	blueoctagon.ac
	bluwedge.ac
	body_xyzisrgb.ac
	delta2.ac
	greenarrow.ac
	pa24-250_blue.ac
	pa24-250_orange.ac
	redwedge.ac
	testrocket.ac