
Contents

Introduction	ix
Chapter 1. Three-dimensional Modeling	1
1.1. Rotation matrices	1
1.1.1. Definition	2
1.1.2. Lie group	3
1.1.3. Lie algebra	4
1.1.4. Rotation vector	5
1.1.5. Adjoint	6
1.1.6. Rodrigues rotation formulas	7
1.1.7. Coordinate system change	8
1.2. Euler angles	11
1.2.1. Definition	11
1.2.2. Rotation vector of a moving Euler matrix	13
1.3. Inertial unit	14
1.4. Dynamic modeling	17
1.4.1. Principle	17
1.4.2. Modeling a quadrotor	18
1.5. Exercises	20
1.6. Corrections	37
Chapter 2. Feedback Linearization	65
2.1. Controlling an integrator chain	65
2.1.1. Proportional-derivative controller	66
2.1.2. Proportional-integral-derivative controller	67
2.2. Introductory example	68
2.3. Principle of the method	69
2.3.1. Principle	69

2.3.2. Relative degree	71
2.3.3. Differential delay matrix	72
2.3.4. Singularities	73
2.4. Cart	75
2.4.1. First model	75
2.4.2. Second model	76
2.5. Controlling a tricycle	78
2.5.1. Speed and heading control	78
2.5.2. Position control	80
2.5.3. Choosing another output	81
2.6. Sailboat	82
2.6.1. Polar curve	83
2.6.2. Differential delay	83
2.6.3. The method of feedback linearization	84
2.6.4. Polar curve control	87
2.7. Sliding mode	87
2.8. Kinematic model and dynamic model	90
2.8.1. Principle	90
2.8.2. Example of the inverted rod pendulum	91
2.8.3. Servo-motors	94
2.9. Exercises	95
2.10. Corrections	107
Chapter 3. Model-free Control	133
3.1. Model-free control of a robot cart	134
3.1.1. Proportional heading and speed controller	134
3.1.2. Proportional-derivative heading controller	136
3.2. Skate car	137
3.2.1. Model	138
3.2.2. Sinusoidal control	140
3.2.3. Maximum thrust control	140
3.2.4. Simplification of the fast dynamics	142
3.3. Sailboat	145
3.3.1. Problem	145
3.3.2. Controller	146
3.3.3. Navigation	152
3.3.4. Experiment	153
3.4. Exercises	155
3.5. Corrections	168

Chapter 4. Guidance	183
4.1. Guidance on a sphere	183
4.2. Path planning	187
4.2.1. Simple example	187
4.2.2. Bézier polynomials	188
4.3. Voronoi diagram	189
4.4. Artificial potential field method	191
4.5. Exercises	192
4.6. Corrections	201
Chapter 5. Instantaneous Localization	221
5.1. Sensors	221
5.2. Goniometric localization	225
5.2.1. Formulation of the problem	225
5.2.2. Inscribed angles	226
5.2.3. Static triangulation of a plane robot	228
5.2.4. Dynamic triangulation	229
5.3. Multilateration	230
5.4. Exercises	231
5.5. Corrections	236
Chapter 6. Identification	243
6.1. Quadratic functions	243
6.1.1. Definition	243
6.1.2. Derivative of a quadratic form	244
6.1.3. Eigenvalues of a quadratic function	245
6.1.4. Minimizing a quadratic function	245
6.2. The least squares method	246
6.2.1. Linear case	246
6.2.2. Nonlinear case	248
6.3. Exercises	250
6.4. Corrections	253
Chapter 7. Kalman Filter	263
7.1. Covariance matrices	263
7.1.1. Definitions and interpretations	263
7.1.2. Properties	266
7.1.3. Confidence ellipse	267
7.1.4. Generating Gaussian random vectors	268
7.2. Unbiased orthogonal estimator	269
7.3. Application to linear estimation	274
7.4. Kalman filter	275

7.5. Kalman–Bucy	279
7.6. Extended Kalman filter	282
7.7. Exercises	283
7.8. Corrections	298
Chapter 8. Bayes Filter	329
8.1. Introduction	329
8.2. Basic notions of probabilities	329
8.3. Bayes filter	332
8.4. Bayes smoother	334
8.5. Kalman smoother	335
8.5.1. Equations of the Kalman smoother	335
8.5.2. Implementation	336
8.6. Exercises	337
8.7. Corrections	345
References	359
Index	361