EE 570: Location and Navigation

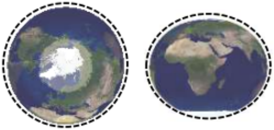
Navigation Mathematics: Kinematics (Earth Surface & Gravity Models)

Stephen Bruder[1] Aly El-Osery[2]

[1]Electrical and Computer Engineering Department, Embry-Riddle Aeronautical Univesity
Prescott, Arizona, USA
[2]Electrical Engineering Department, New Mexico Tech
Socorro, New Mexico, USA

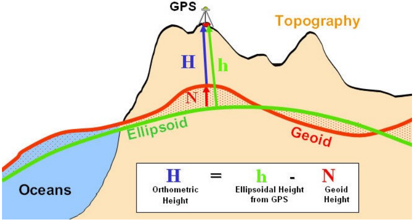
February 4, 2014

- The earth can be modeled as an oblate spheroid
  - A circular cross section when viewed from the polar axis (top view)
  - An elliptical cross-section when viewed perpendicular to the polar axis (side view)



Ratio exaggerated

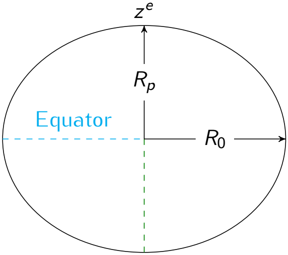
- This ellipsoid (i.e., oblate spheroid) is an approximation of the "geoid"
- The geoid is a gravitational equipotential surface which "best" fits (in the least square sense) the mean sea level



www.nrcan.gc.ca

- WGS 84 provides as model of the earth's geoid
  - More recently replace by EGM 2008
- The equatorial radius radius $R_0 = 6,378,137.0$m
- The polar radius radius $R_p = 6,356,752.3142$m
- Eccentricity of the ellipsoid

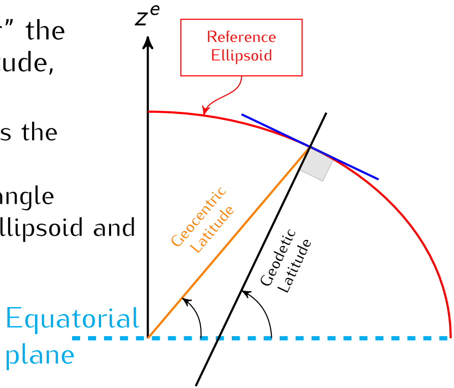
$$e = \sqrt{1 - \frac{R_p^2}{R_0^2}} \approx 0.0818$$



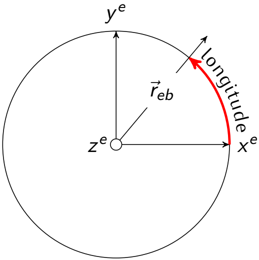
- Flattening of the ellipsoid

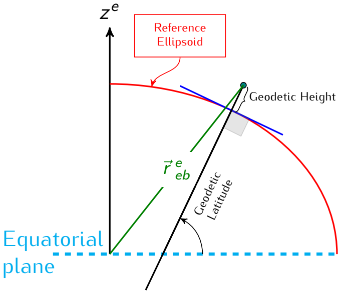
$$f = \frac{R_0 - R_p}{R_0} \approx \frac{1}{298}$$

- We can define a position "near" the earth's surface in terms of latitude, longitude, and height
  - Geocentric latitude intersects the center of mass of the earth
  - Geodetic latitude (L) is the angle between the normal to the ellipsoid and the equatorial plane



- The longitude (λ) is the angle from the x-axis of the ECEF frame to the projection of $\vec{r}_{eb}$ onto the equatorial plane
- The geodetic (or ellipsoidal) height (h) is the distance along the normal from the ellipsoid to the body



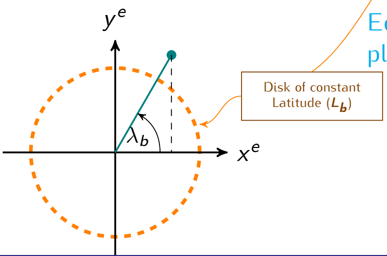


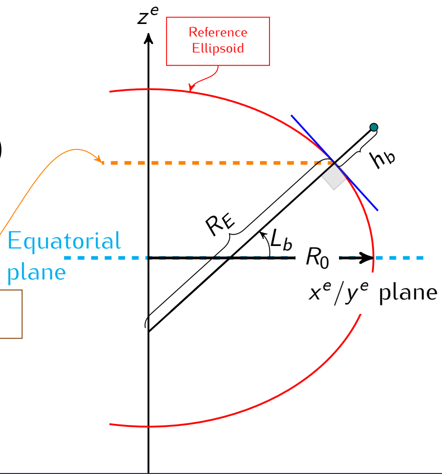
- Transverse radius of curvature

$$R_E(L) = \frac{R_0}{\sqrt{1 - e^2 \sin(L)}} \tag{1}$$

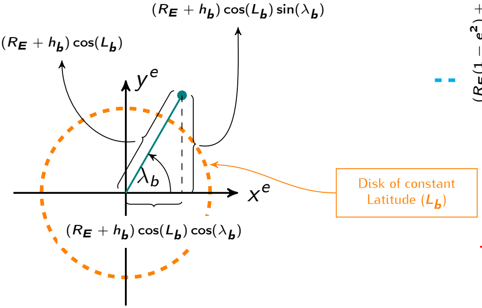
- Meridian radius of curvature

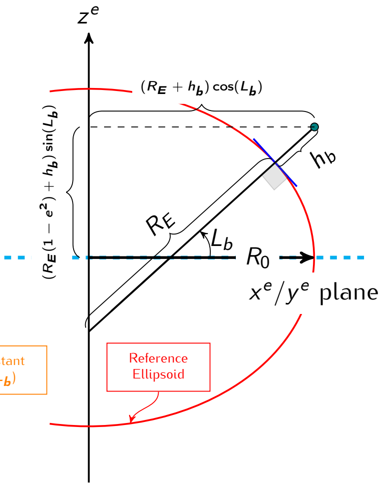
$$R_N(L) = \frac{(1 - e)R_0}{\left(1 - e^2 \sin^2(L)\right)^{3/2}} \tag{2}$$





$$\vec{r}^{\,e}_{eb} = \begin{bmatrix} x^e_{eb} \\ y^e_{eb} \\ z^e_{eb} \end{bmatrix} = \begin{bmatrix} (R_E + h_b)\cos(L_b)\cos(\lambda_b) \\ (R_E + h_b)\cos(L_b)\sin(\lambda_b) \\ (R_E(1-e^2) + h_b)\sin(L_b) \end{bmatrix}$$





- Specific force ($\vec{f}_{ib}$)
  - Non-gravitational force per unit mass (unit of acceleration)
    - Accelerometers measure specific force
- Specific force sensed when stationary (*wrt* earth) is referred to as the acceleration due to gravity ($\vec{g}_b$)
  - Actually, the reaction to this force
- Gravitational force (γ_{ib}) is result of mass attraction
  - The gravitational mass attraction force is different from the acceleration due to gravity

- Relationship between specific force, inertial acceleration, and gravitational attraction

$$\vec{f}_{ib} \equiv \vec{a}_{ib} - \vec{\gamma}_{ib} \tag{3}$$

- When stationary on the surface of the earth
  - Recall case 1: A fixed point in a rotating frame

$$\ddot{\vec{r}}\,^0_{02}(t) = \underbrace{\cancel{\dot{\vec{\omega}}\,^0_{01} \times \vec{r}\,^0_{12}(t)}}_{\dot{\omega}=0} + \vec{\omega}\,^0_{01} \times \left(\vec{\omega}\,^0_{01} \times \vec{r}\,^0_{12}(t)\right)$$

  - Consider frame {0} to be the {i} frame, {1}={e}, and {2}={b} gives

$$\ddot{\vec{r}}\,^i_{ib}(t) = \vec{\omega}\,^i_{ie} \times \left(\vec{\omega}\,^i_{ie} \times \vec{r}\,^i_{eb}(t)\right)$$

  - coordinatizing in the *e*-frame

$$\ddot{\vec{r}}\,^e_{ib}(t) = \vec{\omega}\,^e_{ie} \times \left(\vec{\omega}\,^e_{ie} \times \vec{r}\,^e_{eb}(t)\right)$$

- Thus, when stationary on the surface of the earth the acceleration is due to centrifugal force

$$\vec{a}^{\,e}_{ib} = \Omega^e_{ie}\Omega^e_{ie}\vec{r}^{\,e}_{eb}$$

- Therefore, the acceleration due to gravity is

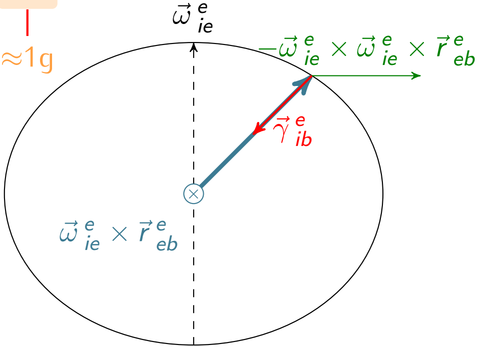
$$\vec{g}^{\,e}_{b} = -\left.\vec{f}_{ib}\right|_{\vec{v}^{\,e}_{eb}=0} = -\Omega^e_{ie}\Omega^e_{ie}\vec{r}^{\,e}_{eb} + \vec{\gamma}^{\,e}_{ib} \tag{4}$$

Specific force

$$\vec{f}_{ib} = \vec{a}_{ib} - \vec{\gamma}_{ib} \tag{5}$$

- Vector diagram

$$\underbrace{\vec{g}^{\,e}_{b}}_{1\mathrm{g}} = \underbrace{-\Omega^e_{ie}\Omega^e_{ie}\vec{r}^{\,e}_{eb}}_{\approx 3\mathrm{mg}} + \underbrace{\vec{\gamma}^{\,e}_{ib}}_{\approx 1\mathrm{g}}$$



- Now, $\vec{\omega}^{\,e}_{ie} = \begin{bmatrix} 0 \\ 0 \\ 1 \end{bmatrix} \omega_{ie}$ and hence, $\Omega^e_{ie} = \begin{bmatrix} 0 & -1 & 0 \\ 1 & 0 & 0 \\ 0 & 0 & 0 \end{bmatrix} \omega_{ie}$, and thus

$$\vec{g}^{\,e}_{b} = \vec{\gamma}^{\,e}_{ib} + \omega^2_{ie} \begin{bmatrix} 0 & 1 & 0 \\ 1 & 0 & 0 \\ 0 & 0 & 0 \end{bmatrix} \vec{r}^{\,e}_{eb}$$

- The WGS 84 model of acceleration due to gravity (on the ellipsoid) can be approximated by (Somigliana model)

$$g_0(L) = 9.7803253359 \frac{\left(1 + 0.001931853 \sin^2(L)\right)}{\sqrt{1 - e^2 \sin^2(L)}} \tag{6}$$

- On March 17, 2002 NASA launched the Gravity Recovery and Climate Experiment (GRACE) which led to the development of some of the most precise Earth gravity models.