

Appendix A

Notation

- 3×1 vectors are represented in **bold**. Example: $\boldsymbol{\omega}$
- The scalar component of a vector is not in bold and has a subscript. Example: ω_x
- 3×3 matrices are shown in [brackets]. Example: $[R]$
- The absolute value of a scalar is shown using one vertical bar on either side of the |variable|. Example: $|B_x|$
- The magnitude of a vector is shown with two vertical bars on either side of the ||**variable**||. Example: $||\mathbf{B}||$
- The 3×3 identity matrix is represented by $[I_{3 \times 3}]$.
- The transpose of a matrix is represented by a superscript T. Example: $[R]^T$
- The trace matrix operation is represented by $\text{tr}()$. Example: $\text{tr}([R])$
- The reference frame of a vector is represented by superscript calligraphy letter before the vector. Example: ${}^{\mathcal{I}}\mathbf{r}$
- The skew-symmetric matrix operator is represented by brackets around the variable and a cross product within the brackets. Example: $[\boldsymbol{\omega} \times]$
- The inertial time derivative $\frac{{}^{\mathcal{I}}d}{dt}$ of a variable is represented by a dot above the variable. Example: $\frac{{}^{\mathcal{I}}d}{dt}\boldsymbol{\omega} = \dot{\boldsymbol{\omega}}$

Appendix B

Explicit Runge-Kutta Integrator Definitions

The family of explicit Runge-Kutta numeric integrators is generalized as follows (repeated from Section 8.1.7.1):

$$y_{n+1} = y_n + h \sum_{i=1}^s b_i k_i \quad (8.26)$$

where

$$\begin{aligned} k_1 &= f(t_n, y_n) \\ k_2 &= f(t_n + c_2 h, y_n + a_{21} k_1) \\ k_3 &= f(t_n + c_3 h, y_n + a_{31} k_1 + a_{32} k_2) \\ &\vdots \\ k_s &= f(t_n + c_s h, y_n + a_{s1} k_1 + a_{s2} k_2 + \dots + a_{s,s-1} k_{s-1}). \end{aligned}$$

A specific Runge-Kutta integrator are is given by its Butcher tableau, which is a standard form of presenting the coefficients used by Equation 8.26. The general form of a Butcher tableau for an explicit Runge-Kutta integrator is shown in Table B.1. The Butcher tableau of each Runge-Kutta integrator used within this dissertation is shown in Tables B.2 through B.7.

Table B.1: The general form of the Butcher tableau for explicit Runge-Kutta Methods [34].

0				
c_2	a_{21}			
c_3	a_{31}	a_{32}		
\vdots	\vdots	\vdots	\ddots	
c_s	a_{s1}	a_{s2}	\dots	$a_{s,s-1}$
	b_1	b_2	\dots	b_{s-1}

Table B.2: The Butcher tableau for explicit fixed RK2 (midpoint method) [34].

0	
1/2	1/2
	0 1

Table B.3: The Butcher tableau for explicit fixed RK3 (Kutta method) [21].

0			
1/2	1/2		
1	-1	2	
	1/6	2/3	1/6

Table B.4: The Butcher tableau for explicit fixed RK4 (Runge-Kutta method) [34].

0				
1/2	1/2			
1/2	0	1/2		
1	0	0	1	
	1/6	2/6	2/6	1/6

Table B.5: The Butcher tableau for explicit fixed RK5 (fixed Dormand-Prince method) [34].

0						
1/5	1/5					
3/10	3/40	9/40				
4/5	44/45	-56/15	32/9			
8/9	19372/6561	-25360/2187	64448/6561	-212/729		
1	9017/3168	-355/33	46732/5247	49/176	-5103/18656	
	35/384	0	500/1113	125/192	-2187/6784	11/84

