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LOCAL PATH PLANNING USING OPTIMAL CONTROL TECHNIQUES

by

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Local Path Planning Using Optimal Control Techniques

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ABSTRACT

The ability of an autonomous vehicle control system to plan a safe, collision-free local path from one vehicle position to another is one of the most important functions. In this thesis, it is shown how a safe obstacle-free local path can be planned using optimal control theory and optimization techniques. The problem is posed as a two point boundary value problem with various problem constraints which control the vehicle behavior in transversing from one point to another. The objective function being minimized is a control performance index which includes vehicle energy saving parameters. Numerous fixed and moving obstacles in the dive plane are introduced and successfully avoided using this technique. Three dimensional path planning is also successfully demonstrated on a 12 state linear model of an underwater vehicle. This technique is shown to be a feasible method for local path planning applications.

THESIS DISCLAIMER

The reader is cautioned that computer programs developed in this research may not have been exercised for all cases of interest. While every effort has been made, within the time available, to ensure that the programs are free of computational and logic errors, they can not be considered validated. Any application of these programs without additional verification is at the risk of the user.

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I. INTRODUCTION

A. GENERAL

The presently forecast missions of an Autonomous Underwater Vehicle (AUV) vary in scope from mine detection and avoidance to surveying the bottom of oceans. Further, it is expected that many of these missions will be conducted within the context of military objectives. Admiral William H. Rowden, Commander Naval Sea Systems Command stated that, "With the NAVSEA (Naval Sea System Command) Integrated Robotics Program about to enter its fifth year of existence, it seems appropriate to look back and ahead to establish a baseline for the promulgation of policy guidelines to facilitate the continuing evolution of this important program." [Ref. 1] He goes on to say that the time has come to incorporate the value of robotics and automation into the Navy's expanding mission. Recent articles of Military Robotics [Refs. 2-6], have pointed out the increased availability of robotic vehicles. These include Remotely Piloted Aircraft, Unmanned Submarines, Teleoperated Combat Vehicles, Cruise Missiles and Teleoperated and Autonomous Weapons.

An extremely important part of the total AUV vehicle control logic is its need to plan and execute a safe passage in the undersea environment. Local path planning is the function provided by an intelligent system, which determines safe, collision-free trajectory of travel between two points, a start point and a target point, for a specific time lapse. One possible total system block diagram that shows how the local path planner could be interfaced, is shown in Figure 1.1. Here, the Global Planning System would provide the Local Path Planner with a series of data sets. Included in the data sets would be destination position, destination time, start position, start time, obstacles and boundaries. In return, the path planner would provide an optimal path based upon the limitations of the vehicle dynamics, power plant efficiency, obstacle field, and required maneuver time.

Numerous techniques have been used to achieve collision free local paths for various vehicle types and manipulators. These include graphical search methods [Refs 7-11], potential field methods [Refs. 12-16] and optimal control theory [Refs. 17, 18]. This thesis is concerned with developing a method of autonomous planning using optimal control theory.

B. PREVIOUS WORK

A basic investigation of local path planning was previously conducted using optimal control theory [Ref. 19]. In that study, major emphasis was placed on the solution of a SISO (Single Input Single Output) problem, a

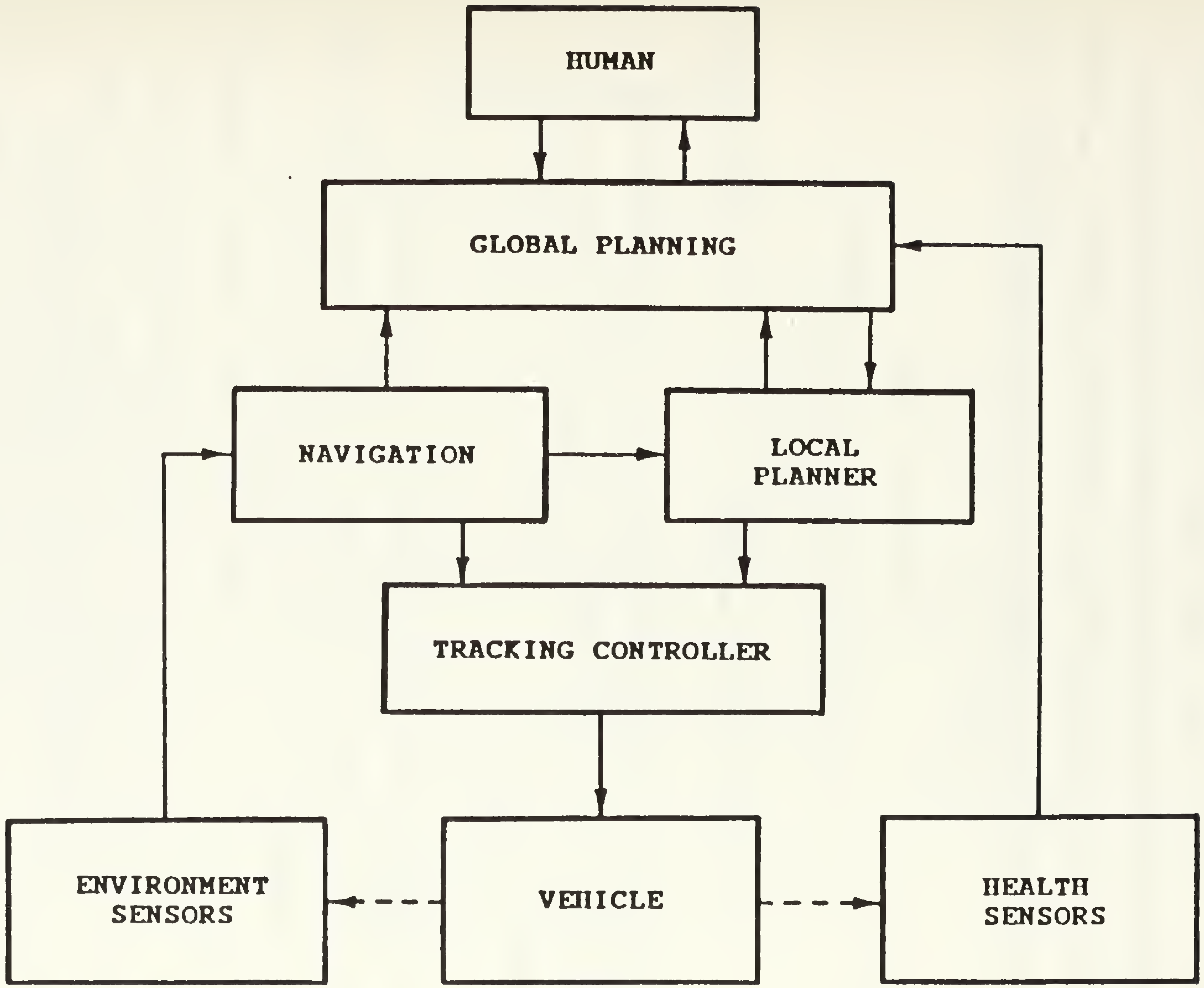

Figure 1.1 Global Planning System

MIMO (Multiple Input Multiple Output) problem and its generalization to a submersible. That work included objective function determination, integration method studies, linear versus nonlinear solution results, computational expense and an obstacle avoidance solution with one fixed obstacle. The objective function used for optimization was a quadratic performance index of the form:

$$J = \int_0^{FINTIM} (\underset{\sim}{X}^T \underset{\sim}{Q} \underset{\sim}{X} + \underset{\sim}{U}^T \underset{\sim}{R} \underset{\sim}{U})dt$$

where,

$\underset{\sim}{U}$ = the control vector; and

$\underset{\sim}{X}$ = desired states-actual states (i.e. state error)

The nonlinear hydrodynamic equations of motion for the Autonomous Underwater Vehicle being studied were of the following form:

$$\underset{\sim}{M}\ddot{X} + f(\dot{\underset{\sim}{X}}, \underset{\sim}{X}) = g(\underset{\sim}{U})$$

The "best" solution was obtained by minimizing the objective function (J) in order to find the best $\underset{\sim}{U}(t)$ and $\underset{\sim}{X}(t)$ values.

The Automatic Design Synthesis (ADS) Fortran Program [Ref. 20] was utilized for problem optimization and the Dynamic Simulation Language (DSL) Program [Ref. 21] was utilized for objective function calculations and integrations of the vehicle dynamic equations. These software programs were made to be interactive and now perform as one software package [Ref. 22]. The combined package is called ADSL and has been incorporated on the IBM 3033 Mainframe Computer System at the Naval Postgraduate School. The basic optimization approach was as follows:

1. Discretize the control vector into a time-wise uniform distribution of control signals (Figure 1.2)

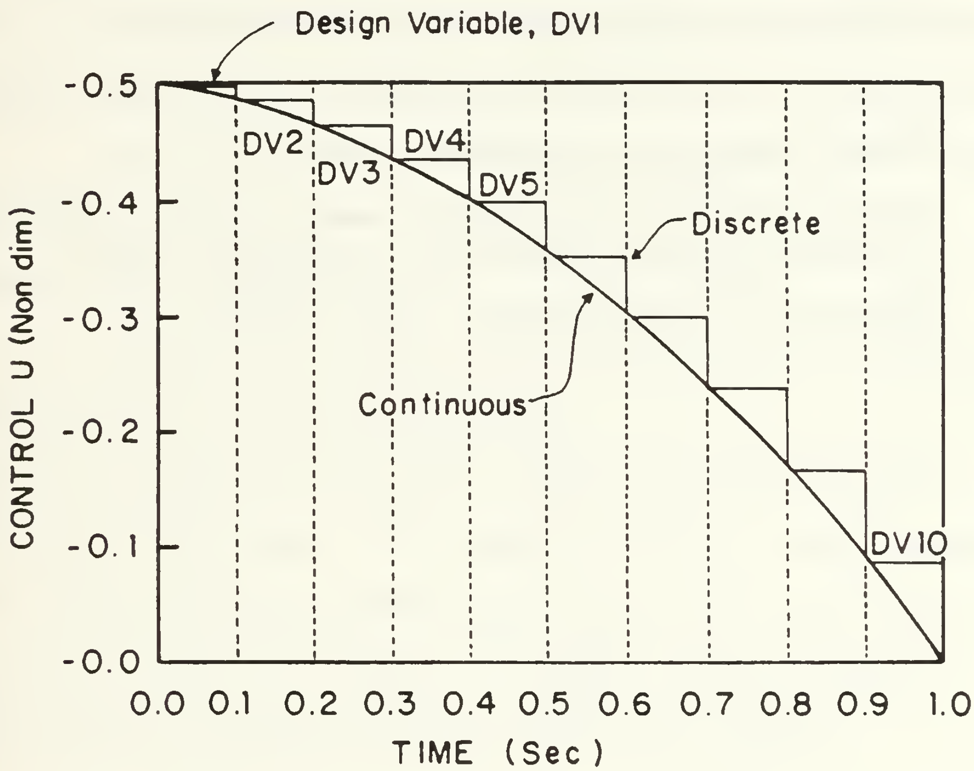

Figure 1.2 Discrete vs. Continuous Controls

2. Determine the best control sequence via an optimization routine based upon the objective function and problem constraints.

In the two-dimensional problem (dive plane only), the vehicle was ordered to achieve an ordered depth of 17.425

feet using minimum bow and stern plane deflections. Additionally, the vehicle was required to have a minimum pitch angle at its final end condition. The control vector ($\underset{\sim}{U}$) was the bow and stern plane angles, while the $\underset{\sim}{X}$ vector was the x and z positions of the vehicle and velocities in the x and z directions.

C. AIM OF THE PRESENT STUDY

This thesis is concerned with furthering the understanding of local path planning using optimal control theory. The purpose of this work is to:

1. Further develop the planning level control logic to consider three-dimensional maneuvers, and

2. Evaluate the performance of this logic.

II. METHOD OF APPROACH

The basic approach was as follows:

1. Improve the treatment of obstacles, both fixed and moving in the two-dimensional problem.

2. Determine the best set of optimization program options based on computational cost, robustness, flexibility and solution accuracy in the two-dimensional problem.

3. Select guidance for maneuvering time (FINTIM) and determine how it effects problem solution in the two-dimensional problem.

4. Evaluate two dimensional versus three dimensional computational costs and accuracy.

The basic assumption in this study was that the work previously done [Ref. 19] remained valid. Specifically, that the integration method selected, the step size, objective function, number of design variables and optimization program options remained relevant.

III. OBSTACLE AVOIDANCE

The approach previously presented [Ref. 19] was to compute the distance to the obstacle at ten equally divided time intervals from start time to the time of closest obstacle approach. These updated distances were then incorporated into the optimization algorithm for constraint value determination. ADSL placed constraint equations into the algorithm in the form:

$$G_j(k) = 0 \qquad j = 1, m$$

which in the actual program is:

Gk(k) = (avoidance zone) - (updated vehicle distance)

The time interval for distance calculations was determined based on the FINTIM and clock time as follows:

```
If (time.ge.0.0.and.le.xobs/u) then
time1 = xobs/u
qn = time/(time1/10. - delt/10000.)
d = int(qn + 1)
dist(d) = sqrt((xpos-xobs) x (zpos-zobs))
g(d) = 1. - dist(d)
```

where:

time = DSL clock time

xobs = x position of the obstacle

delt = integration time step interval

xpos = x position of the vehicle

u = vehicle velocity in the x direction

dist(d) = computed distance from the vehicle to the obstacle

zpos = z position of the vehicle

zobs = z position of the obstacle

g(d) = constraint value placed in optimization routine

The problem with this approach is that the further an obstacle is from the start position, the longer the time intervals become for obstacle distance calculations. This is satisfactory for a single fixed obstacle but for multiple obstacles, this method results in inadequate distance computations. This is because the closer obstacles do not have sufficient constraint inputs compared to the distant obstacles. As a result, the distant obstacles tend to dominate the solution. Using multiple "if" statements in this logic is also computationally expensive and failed when used with three or more obstacles.

Another inherent problem was that distances were not computed after the time of closest approach. This sometimes resulted in maneuvers with distances to the obstacle that violated the avoidance zone regions after the first time of closest approach.

A better method is to continuously compute distances to the obstacle, independently of FINTIM, but dependent on FINTIM step intervals. This approach worked very well and was adopted for all further analysis. An additional advantage to this approach is that only one constraint assignment was needed for each obstacle vice ten.

The computational time for obstacle avoidance varies as the number of obstacles increases. The motivation for this study was to determine if this approach was computationally too expensive to remain as a viable approach. Figure 3.1 shows the computational cost for one to seventeen fixed obstacles. The computational time is based on the virtual machine time for the IBM 3033 system at the Naval Postgraduate School. In all cases, the final depth was the desired depth of 17.425 feet.

Various optimization techniques have various computational costs; however, the times in Figure 3.1 are based upon the final optimization option selected for this thesis. The selection criteria with results will be presented in the following chapter.

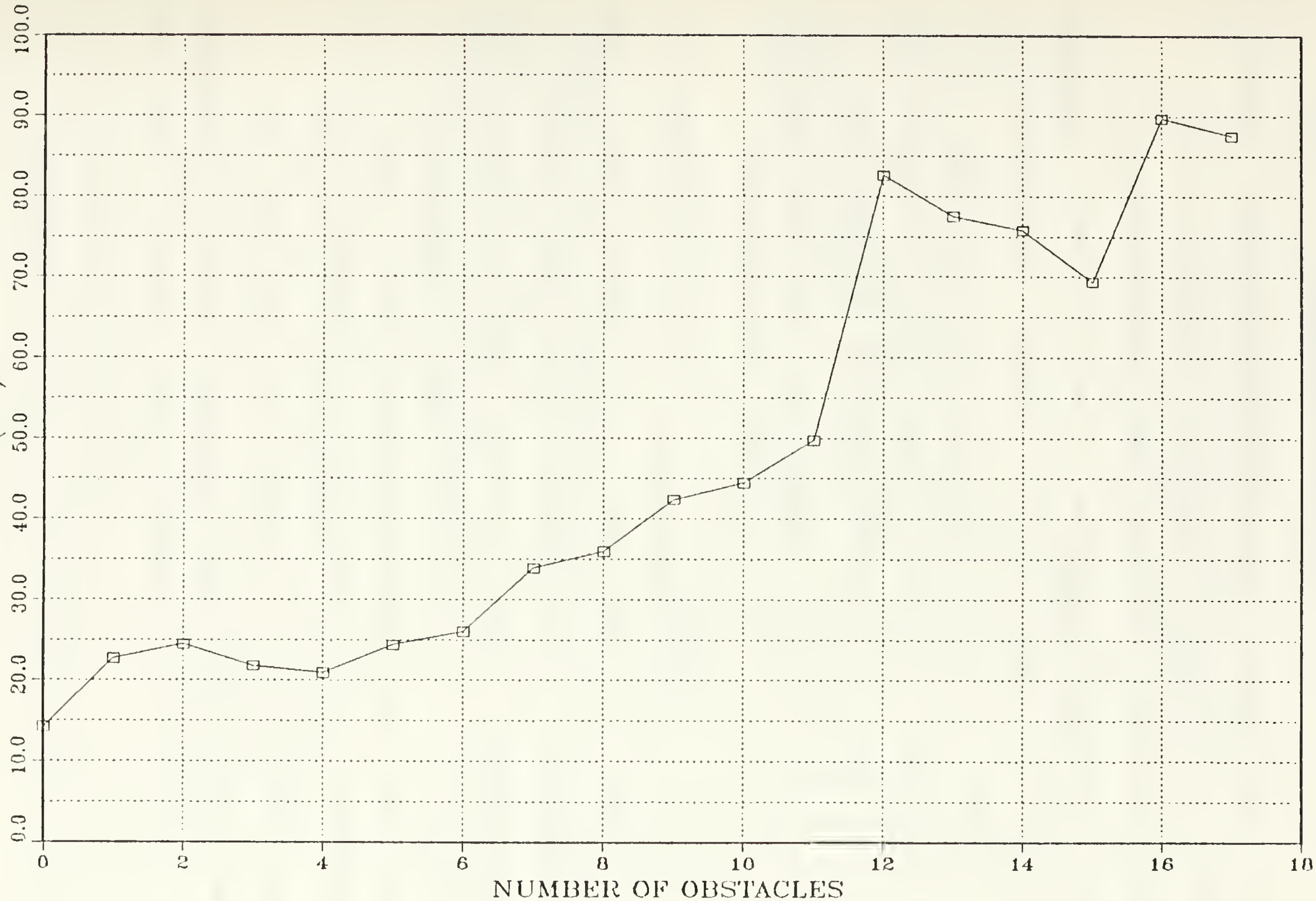

Figure 3.1 Fixed Obstacle Computational Results

IV. OPTIMIZATION OPTIONS

The ADS (Advanced Design Synthesis) Program allows for the selection of numerous optimization techniques for problem solution. There are three levels by which to select a particular technique. The three levels are the strategy level, optimizer level and the one-dimensional search level. Table 1 lists the various levels and the various methods contained in each. Figure 4.1 identifies the large number of possible algorithm combinations allowed. Vanderplaats provides a detailed discussion of the various methods and algorithms in Reference 23.

A. CLUSTERED FIXED OBSTACLE TEST

In order to be effective as a path planning algorithm, it is necessary for the program option to be robust and flexible enough to solve problems involving numerous fixed obstacles as well as moving obstacles. Therefore, an initial test was conducted where the number of obstacles in the vehicle's path were varied from one to seventeen. Program option 057 was selected first based upon the recommendation of the previous study, which involved one fixed obstacle in the vehicle's path. Option 057 appeared acceptable until a four obstacle field was encountered. At this point, the option failed to reach an adequate

IOPT	OPTIMIZER
1	Fletcher-Reeves
2	Davidon-Fletcher-Powell (DFP)
3	Broydon-Fletcher-Goldfarb-Shanno (BFGS)
4	Method of Feasible Directions
5	Modified Method of Feasible Directions

STRATEGY	**ISTRAT**	**IOPT**	**1**	**2**	**3**	**4**	**5**
None	0		X	X	X	X	X
SUMT, Exterior	1		X	X	X	0	0
SUMT, Linear Extended Interior	2		X	X	X	0	0
SUMT, Quadratic Extenden Interior	3		X	X	X	0	0
SUMT, Cubic Extended Interior	4		X	X	X	0	0
Augmented Lagrange Multiplier Meth.	5		X	X	X	0	0
Sequential Linear Programming	6		0	0	0	X	X
Method of Centers	7		0	0	0	X	X
Sequential Quadratic Programming	8		0	0	0	X	X
Sequential Convex Programming	9		0	0	0	X	X

ONE-DIMENSIONAL SEARCH	**IONED**					
Golden Section Method	1	X	X	X	0	0
Golden Section + Polynomial	2	X	X	X	0	0
Polynomial Interpolation (bounded)	3	X	X	X	0	0
Polynomial Extrapolation	4	X	X	X	0	0
Golden Section Method	5	0	0	0	X	X
Golden Section + Polynomial	6	0	0	0	X	X
Polynomial Interpolation (bounded)	7	0	0	0	X	X
Polynomial Extrapolation	8	0	0	0	X	X

NOTE: An X denotes an allowed combination of algorithms.

Figure 4.1 Allowable ADS Algorithm Combinations

TABLE 1. ADS LEVEL OPTIONS

STRATEGY (ISRRAT)

0 - None

1 - SUMT, Exterior Penalty Function

2 - SUMT, Linear Extended Interior

3 - SUMT, Quadratic Extended Interior

4 - Cubic Extended Interior

5 - Augmented Lagrange Multiplier Method

6 - Sequential Linear Programming

7 - Method of Centers

8 - Sequential Quadratic Programming

9 - Sequential Convex Programming

OPTIMIZER (IOPT)

1 - Fletcher-Reeves

2 - Davidon-Fletcher-Powell (DFP)

3 - Broydon-Fletcher-Golfarb-Shanno (BFGS)

4 - Method of Feasible Directions

5 - Modified Method of Feasible Directions

ONE-DIMENSIONAL SEARCH (IONED)

1 - Golden Section Method

2 - Golden Section and Polynomial

3 - Polynomial Interpolation, bounded

4 - Polynomial Extrapolation

5 - Golden Section Method

6 - Golden Section and Polynomial

7 - Polynomial Interpolation, bounded

8 - Polynomial Extrapolation

solution. Option 133 was then selected based upon Olson's work [Ref. 22]. Option 133 is more robust than option 057 and it appeared to be very well suited for this problem until the ten obstacle field was encountered. This method achieved the correct ordered depth; however, it violated many of the obstacle avoidance zones. It was apparent, at this point, that all program options would have to be tested in order to determine the most appropriate algorithm.

A test was conducted to determine if any of the one hundred and twelve program options could solve a seventeen obstacle problem. The complete test problem required the program option to solve a seventeen obstacle field problem with FINTIM set at seven seconds and an ordered depth of 17.425 feet. Each obstacle had a one foot radius avoidance zone. The results of that study are presented in Table 2.

TABLE 2. 17 OBSTACLE TEST RESULT

PROGRAM OPTION	COMPUTATIONAL COST (sec)	DEPTH (feet)
311	87.92	17.425
312	92.56	17.425
313	58.78	17.425
314	73.51	17.425
321	146.23	17.425
322	142.32	17.425
323	115.11	17.425
324	165.12	17.425
331	167.25	17.425
332	136.84	17.425
333	151.90	17.425
334	120.78	17.425
411	76.19	17.425
412	96.00	17.421
413	42.99	17.425
414	64.92	17.424
421	116.61	17.425
422	140.87	17.425
423	82.18	17.425
424	94.39	17.425
431	115.67	17.425
432	143.50	17.425
433	81.64	17.425
434	97.29	17.425
512	70.17	17.425
534	48.87	17.449

Of the one hundred and twelve program options, only twenty six achieved a correct solution. The computational time varied significantly among the various successful program options. In some cases, the exact depth was not achieved; however, all results were considered excellent.

After determining which algorithms could solve the seventeen obstacle problem, it was then necessary to verify that cases involving various obstacle combinations from one to sixteen were solvable by these methods. It may seem intuitively obvious that if an algorithm can achieve a solution involving seventeen obstacles that it can solve all other cases from one obstacle to sixteen obstacles. Contrary to intuition, this is not the case. For example, program option 313, which had a relatively small computational cost, successfully solved the seventeen obstacle problem but failed to achieve the correct depth when an eleven obstacle field was encountered.

In conducting the varying fixed obstacle investigation, obstacles were purposefully placed in various positions in the field in order to ensure that obstacle position had no negative effect upon the problem solution. This was significant because program option 057 (method chosen in the previous study), failed when it encountered an obstacle field with three fixed obstacles. Two obstacles were placed in the vehicle's path and one was placed far from the vehicle's path. The obstacle far away from the vehicle's path was determined to be the cause of failure because the algorithm successfully solved a problem with three obstacles when all three were placed near the vehicle's path. Using the cases of one to seventeen obstacles, the cases were further reduced from 26 to 22. Program options 313, 413, 534, and 314 were eliminated.

B. IMPOSSIBLE FIELD TEST

After an investigation of the varying obstacle test, the reduced list of programs were subjected to an impossible problem. Four obstacles were placed in the vehicle's path with nine, five, three, and six feet radii. They were placed in such a way that the algorithm could not achieve the correct solution in the allotted time. It is important to point out that a correct solution would have been obtainable if the simulation time was increased. The motivation for this study was to determine the failure modes of various algorithms. It was evident from this study that some algorithms, namely those which employed a strategy of Sequential Unconstrained Minimization using the Cubic Extended Interior Penalty Function Method, were more sensitive to achieving the desired depth constraints, when they were imposed as equality constraints. The algorithms which employed the strategy of Sequential Unconstrained Minimization using the Quadratic Extended Interior Penalty Function Method, were more sensitive in avoiding obstacle avoidance zones when they were imposed as inequality constraints. Figure 4.2 illustrates the performance of three different algorithms in solving this problem. Of the algorithms with relatively small computational costs, program option 311 did the best job of avoiding the avoidance zones.

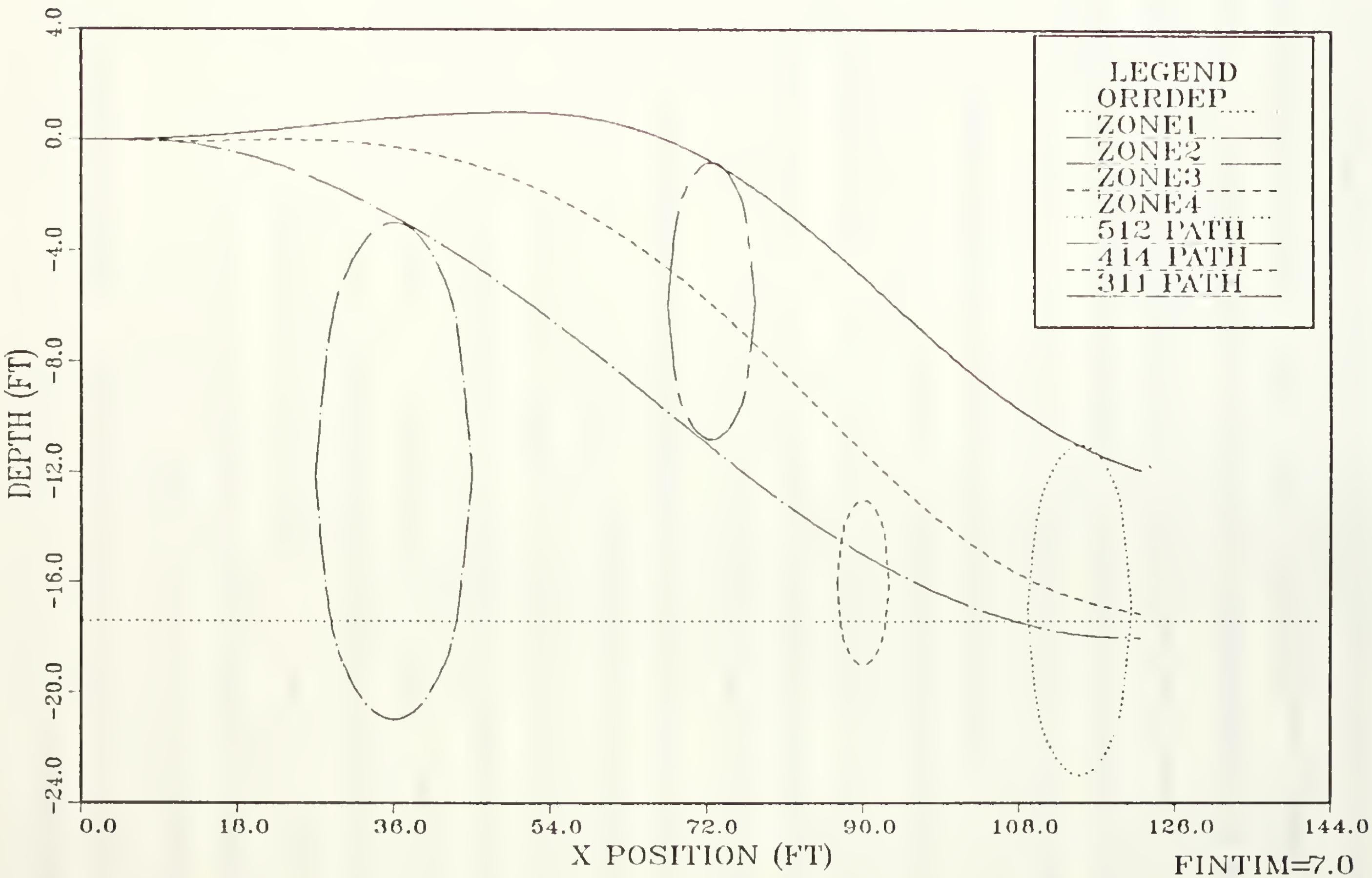

Figure 4.2 Impossible Test Algorithm Comparison

With the impossible field test, computational cost uniformly increased compared to the four obstacle problem with smaller avoidance zones. Program option 311 had a computational cost of 74.30 Virtual Machine second in the impossible problem; however, with four obstacles it took 21 seconds (Figure 3.1). Figure 4.3 is the solution result obtained if FINTIM is increased to 15.0. Although FINTIM was more than doubled, the computational cost did not significantly increase. With FINTIM set to 15.0, the virtual machine time was 76.51 seconds.

C. SELECTION RESULT

Program option 311 with a strategy of Sequential Unconstrained Minimization using the Quadratic Extended Interior Penalty Function Method; an Optimizer using the Fletcher-Reeves algorithm and a one-dimensional search method using the Golden Section Method was chosen as the best algorithm. It was selected because it had the least computational cost of any algorithm which could solve the seventeen obstacle test problem and was very sensitive to the obstacle avoidance zones. In other words, it proved to be very good at finding a safe, collision-free path between the start condition and the end condition.

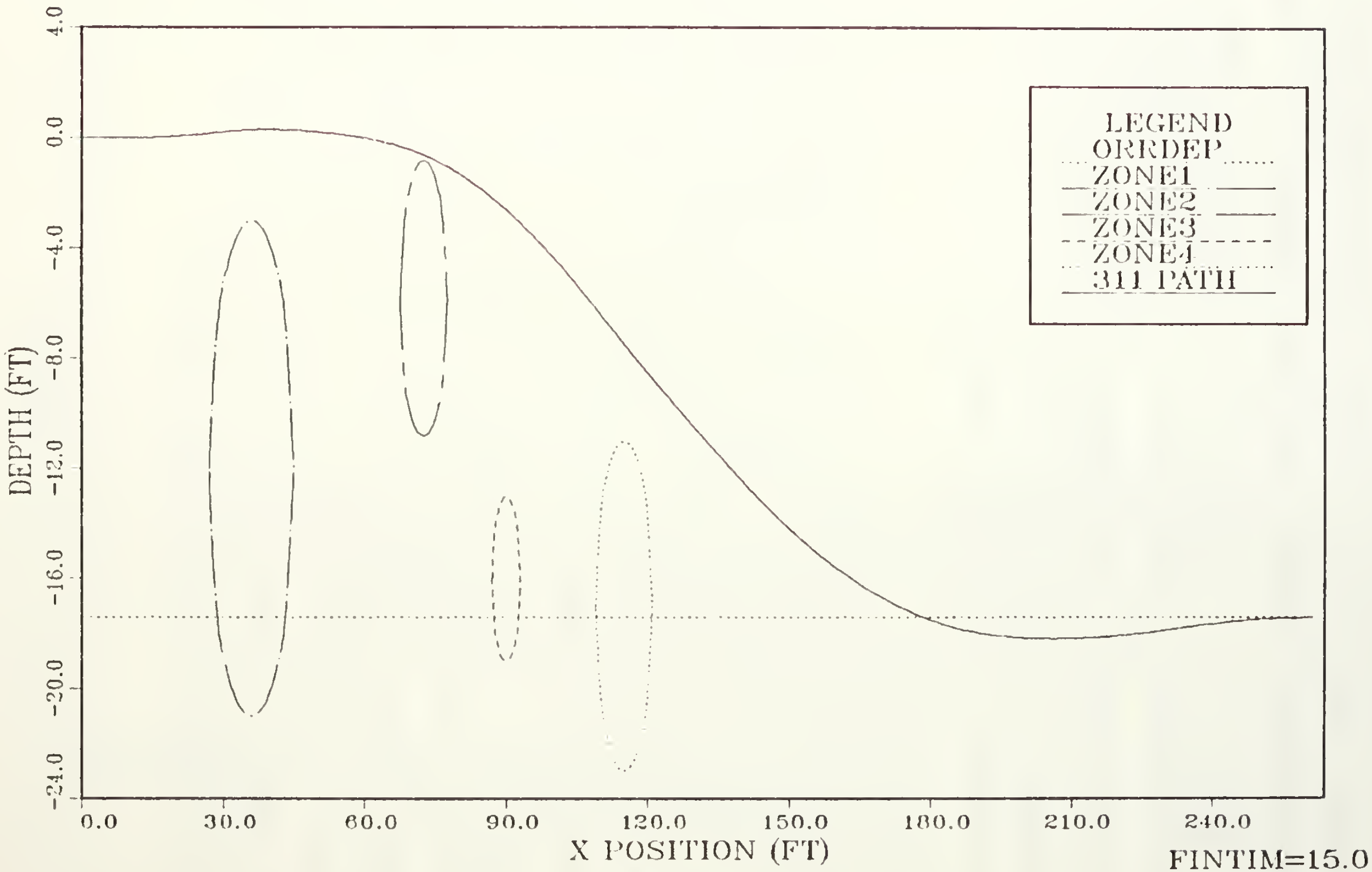

Figure 4.3 Solution of Impossible Test with Increased FINTIM

V. EVALUATION OF MANEUVERING TIME (FINTIM)

Qualitatively, there are two possible FINTIM effects. Those which are associated with a small FINTIM and those which are associated with an excessively large FINTIM. The net effect of too small a FINTIM is an over constraining of the problem, which leads to a violation of problem constraints and excessive computational time.

Two things happen when the FINTIM is too large. The solution adheres more to problem constraints and the computational cost decreases. The mission objectives of the vehicle (i.e., loitering at start position), are significant considerations, which FINTIM selection must take into account. Therefore, FINTIM is a critical parameter which effects problem solution and also, when chosen correctly, significantly reduces computer computational costs. The selection of FINTIM poses an important problem which requires solving in view of high-level vehicle objectives.

One guideline for selecting FINTIM is to select it based on the time required to achieve a solution while transversing an obstacle-free field, then arbitrarily increase FINTIM to allow for obstacle avoidance. The following results using program options 533 points out the importance of choosing a correct FINTIM. As can be seen in

Figure 5.1, FINTIM can adversely affect the problem solution if the time allotted is not large enough to achieve the desired result. When FINTIM is chosen to be 6.0 non-dimensional time units (NTU), the avoidance zone constraint for zone 3 is violated and the desired depth of 17.425 feet is exceeded. When FINTIM is increased to 7.0 NTU, avoidance zone constraints are violated for zone 1 and zone 3 and the desired depth is not achieved. However, the severity of the violations are not as blatant. When FINTIM is increased to 8.0 NTU, the desired problem solution is obtained. Table 3 presents the computational costs associated with each FINTIM selection. Note that the optimization problem is easier with more maneuvering time, therefore the computational cost is less.

TABLE 3. FINTIM COMPUTATIONAL COST

FINTIM	TIME (sec)
6.0	95.06
7.0	76.75
8.0	32.43

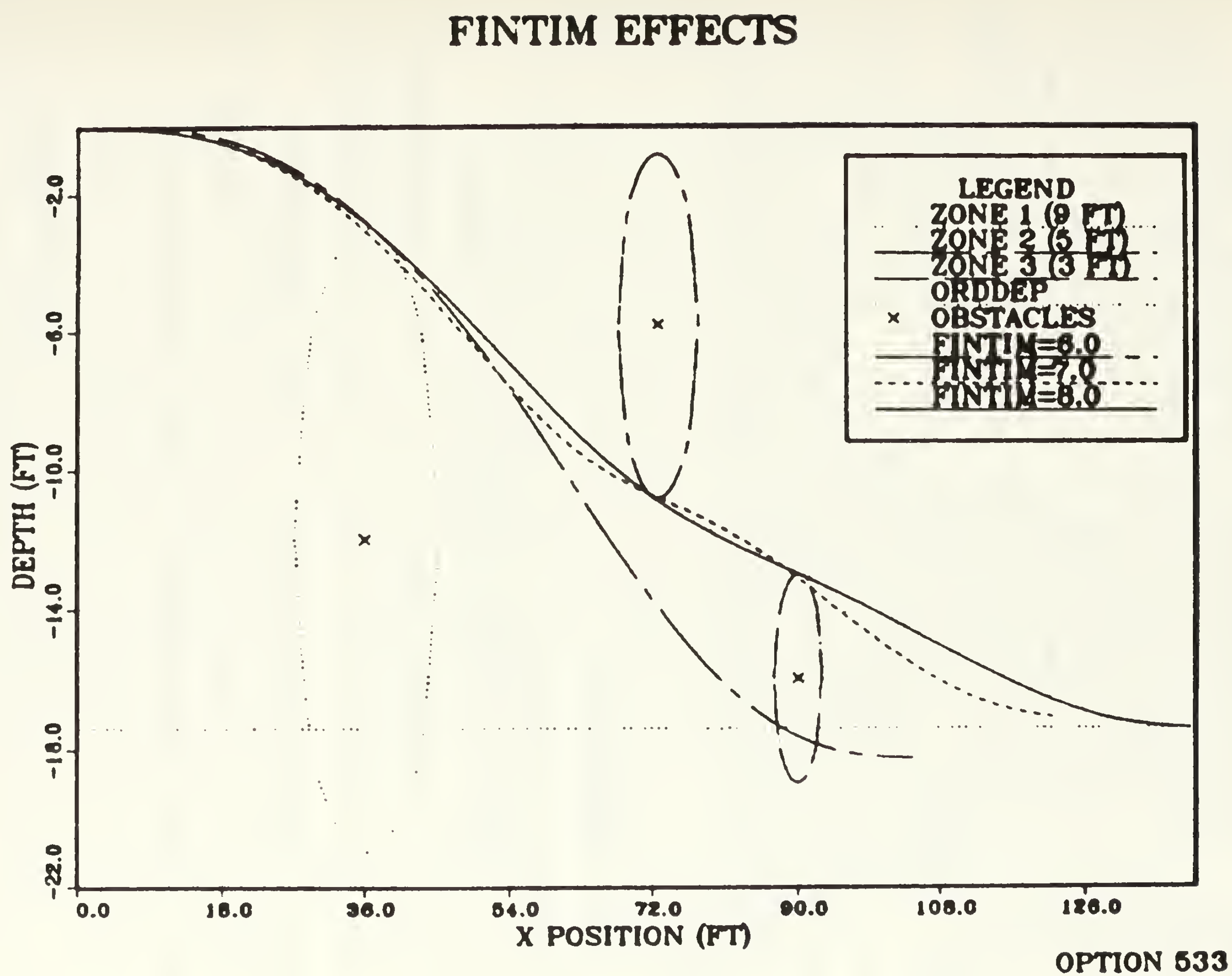

Figure 5.1 FINTIM Effects

VI. PROGRAMMING FOR THREE DIMENSIONS

In programming for three dimensions, we not only optimize the problem to obtain bow plane and stern plane commands, but we also optimize to obtain the rudder commands. In order to achieve the desired result, it was necessary to increase the number of design variables for the rudder in the linear model. The problems discussed previously, have all been solved using ten discretizations (design variables) for the stern plane and bow plane inputs. In the three-dimensional work, the number of design variables were arbitrarily increased to twenty (less discretizations would not achieve a satisfactory result).

A. SIDE CONSTRAINTS

Additional constraints were added to the problem in order to ensure reasonable vehicle control surface reactions. The maximum rudder angles were set at plus or minus thirty degrees. In order to ensure this, the side constraint approach was invoked. These values were assigned to the Design Variable Lower Bound (VLB) and the Design Variable Upper Bound (VUB) ADS parameters.

B. EQUALITY CONSTRAINTS

Six additional equality constraints were needed to achieve the desired y position and the desired vehicle condition (yaw and roll) at the desired end condition.

C. CONSTRAINT SCALING

Sanders [Ref. 19] points out that constraint weighting is important in achieving the desired results. This is even more crucial in a three-dimensional problem solution because of the increased number of constraints on yaw, roll, rudder control and y positioning. It appears that problem sensitivity to constraint weighting is also increased. In order to achieve the desired solution result, it was necessary to adjust constraint scaling factors until all constraint conditions were satisfactorily obtained. Table 4 shows the constraint scaling factors used in the full three-dimensional linear model.

TABLE 4. CONSTRAINT SCALING FACTORS

CONSTRAINT	SCALING FACTOR
depth	0.5
y position	2.5
pitch	1.0
yaw	1.0
roll	1.0
minimum depth	1.0

D. LINEAR/NONLINEAR DYNAMICS

Figure 6.1 illustrates the nonlinear model behavior when using control inputs for bow plane, stern plane, and rudder from the optimized linear model. It is evident that these commands are invalid for the full scale nonlinear model since the final objective state is not closely met. Therefore, the essential dynamics of the linear model are not valid in three dimensions as might be suggested from the results of the previous study. However, even though the control surface inputs are invalid, the vehicle state trajectory is valid because the path chosen achieved the desired result. For a desired position of y=40.0 feet and depth =-20.0 feet, the obtained result was y=40.269 feet with a depth of -20.699 feet. These values can be fine tuned by varying the scaling factors. Figures 6.2 and 6.3 illustrate the control inputs to the linear model and Figure 6.4 illustrates the linear model response to those inputs.

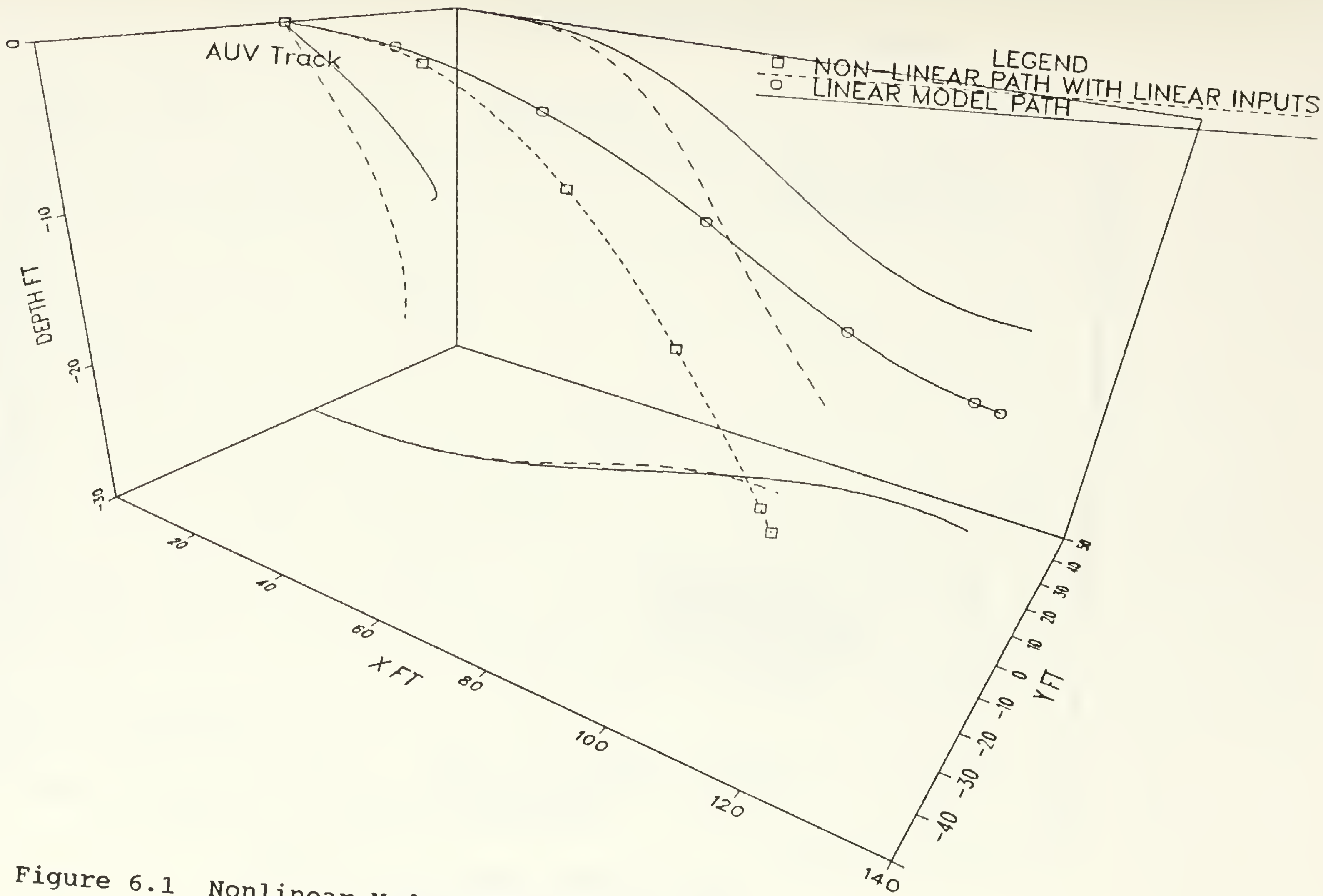

Figure 6.1 Nonlinear Model Maneuver with Linear Control Inputs

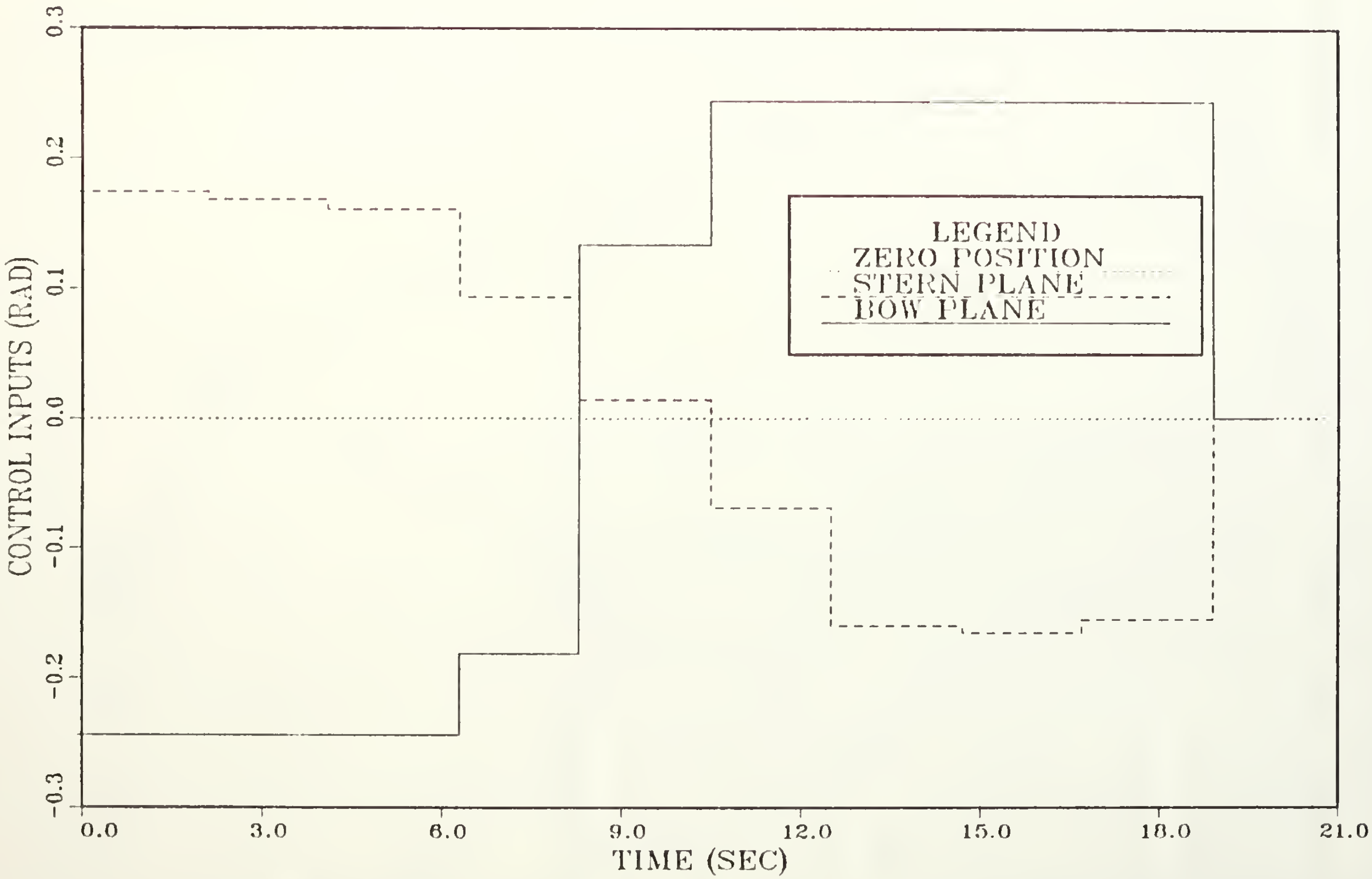

Figure 6.2 Bow and Stern Plane Control Inputs

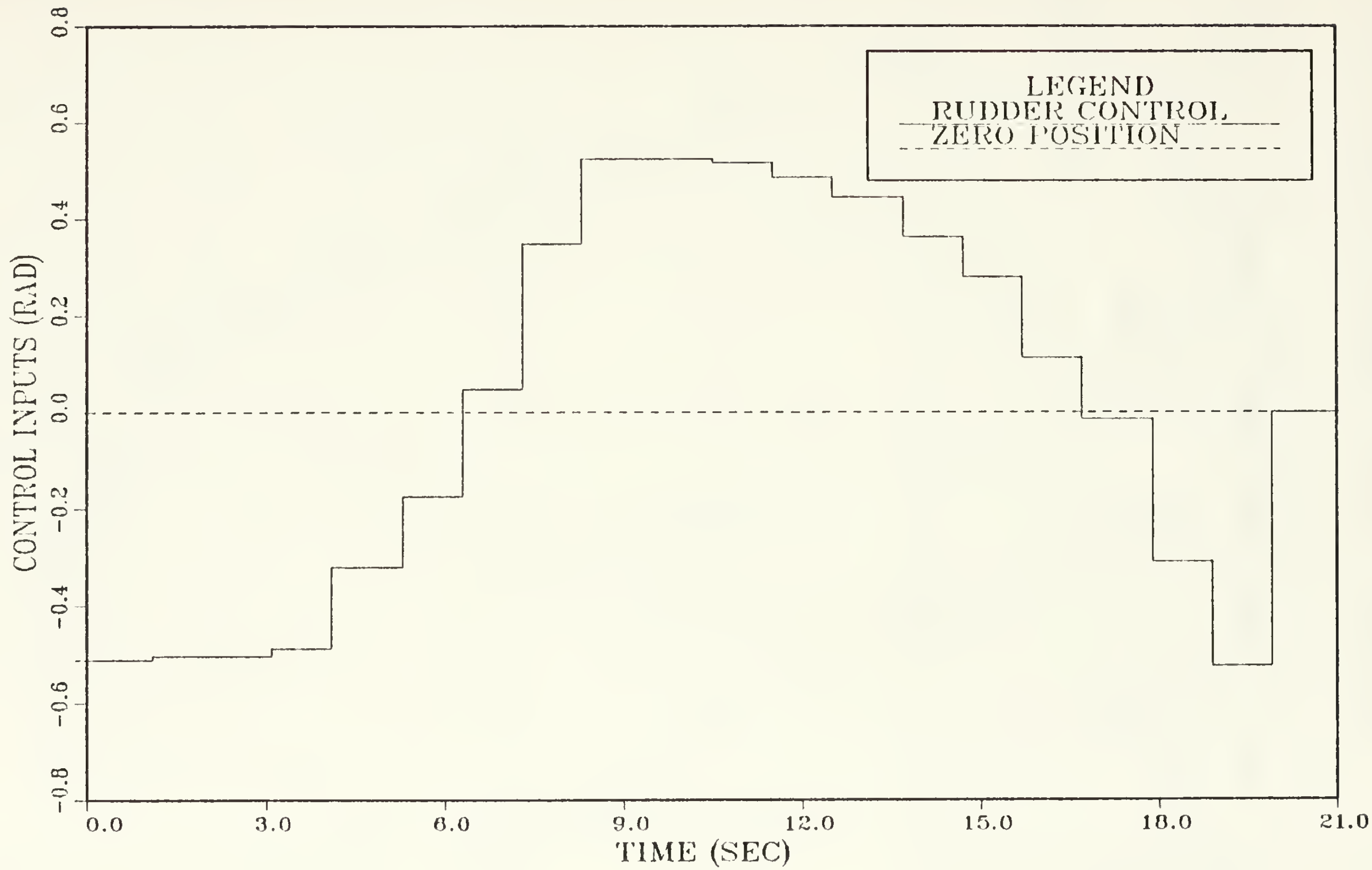

Figure 6.3 Rudder Control Input

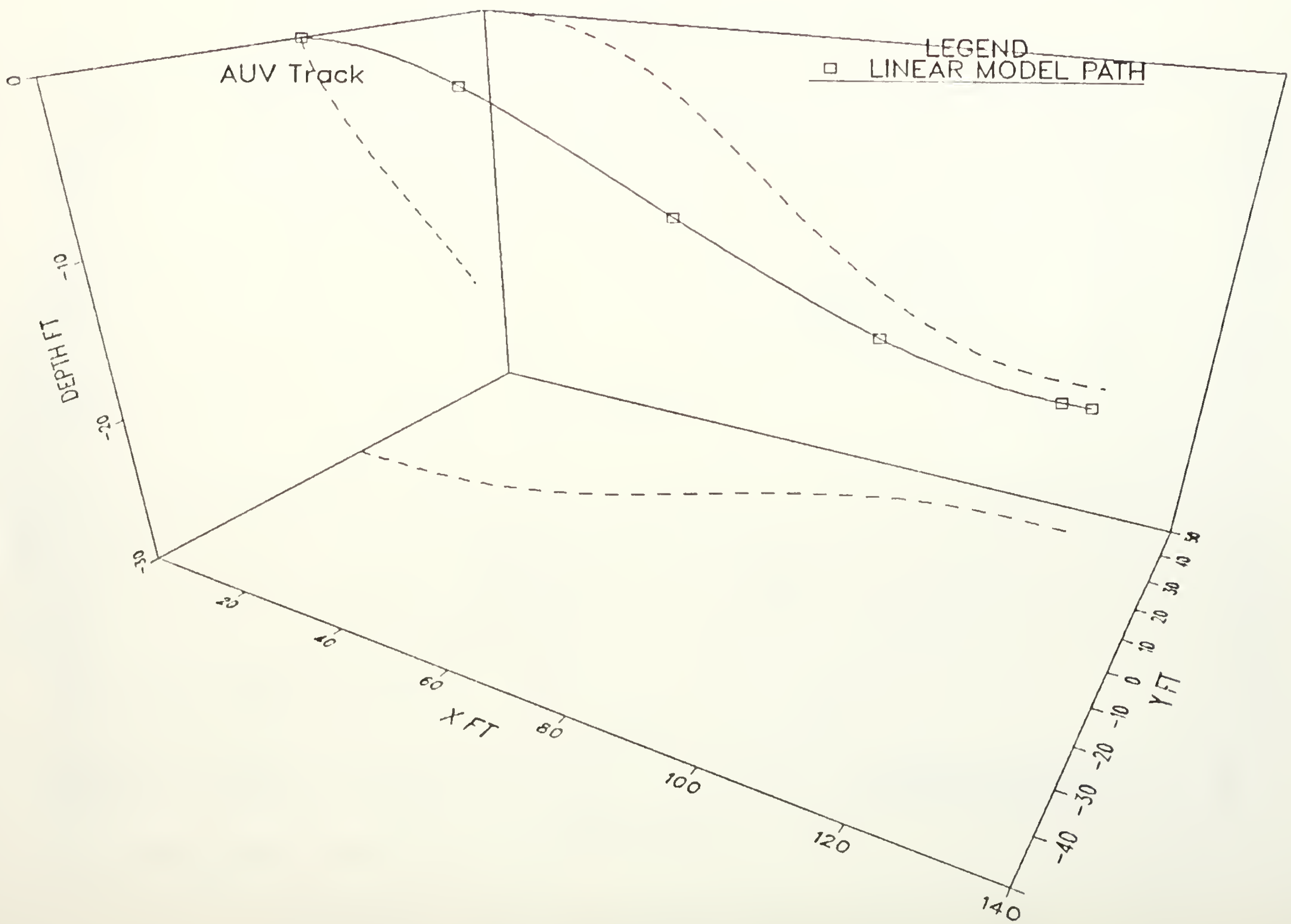

Figure 6.4 Linear Model Maneuver

E. THREE-DIMENSIONAL COMPUTATIONAL COSTS

Table 5 compares the virtual machine time of the full scale linear model with no obstacles as compared to the full scale nonlinear model with no obstacles.

TABLE 5. LINEAR VS. NONLINEAR COMPUTATIONAL COSTS

	LINEAR (sec)	NONLINEAR (sec)
DIVE PLANE ONLY	14.23	108.81
FULL 3D	130.34	370.61

VII. VALIDATION RUNS

As previously mentioned, in order to validate the selected optimization configuration, fixed obstacles were placed at various positions in the AUVs field of view with 1.0 foot radius avoidance zones around the obstacles. Figure 7.1 to 7.8 illustrate the paths chosen by the 311 algorithm to avoid the obstacles and their avoidance zones for various obstacle positions.

The moving obstacles were simulated using rectilinear average velocity equations of the form:

$$s = Vt$$

where:

s = position of obstacle (X and/or Y)

V = constant velocity

t = time of travel

Figures 7.9 to 7.11 present the distance between the AUV and the moving obstacle(s) as a function of time. As seen, the algorithm chooses a path in both cases which avoids impact. Table 6 presents the computational cost comparison of various obstacle case(s). Some three-dimensional linear and non-linear state trajectory results were presented earlier.

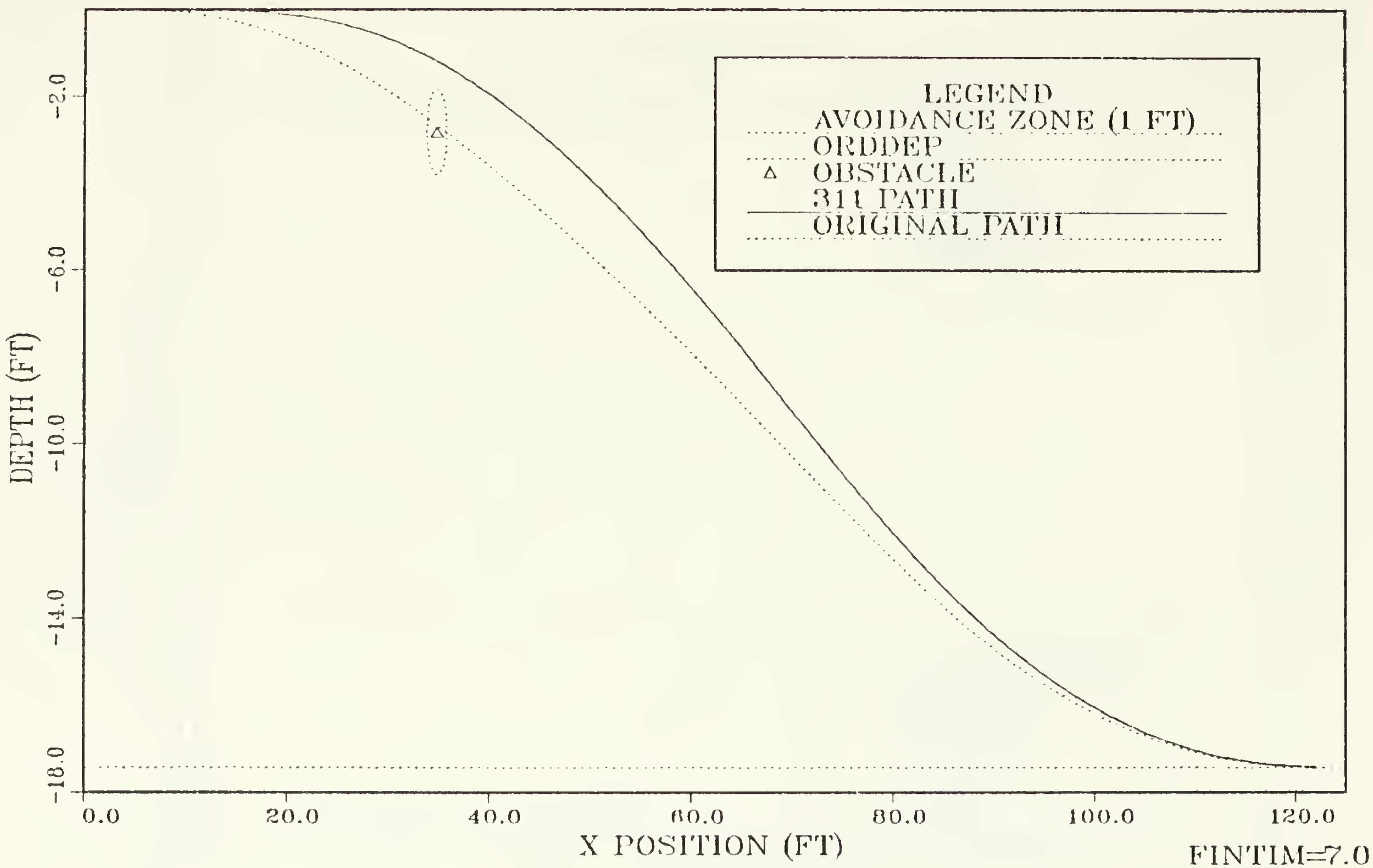

Figure 7.1 One Obstacle Solution

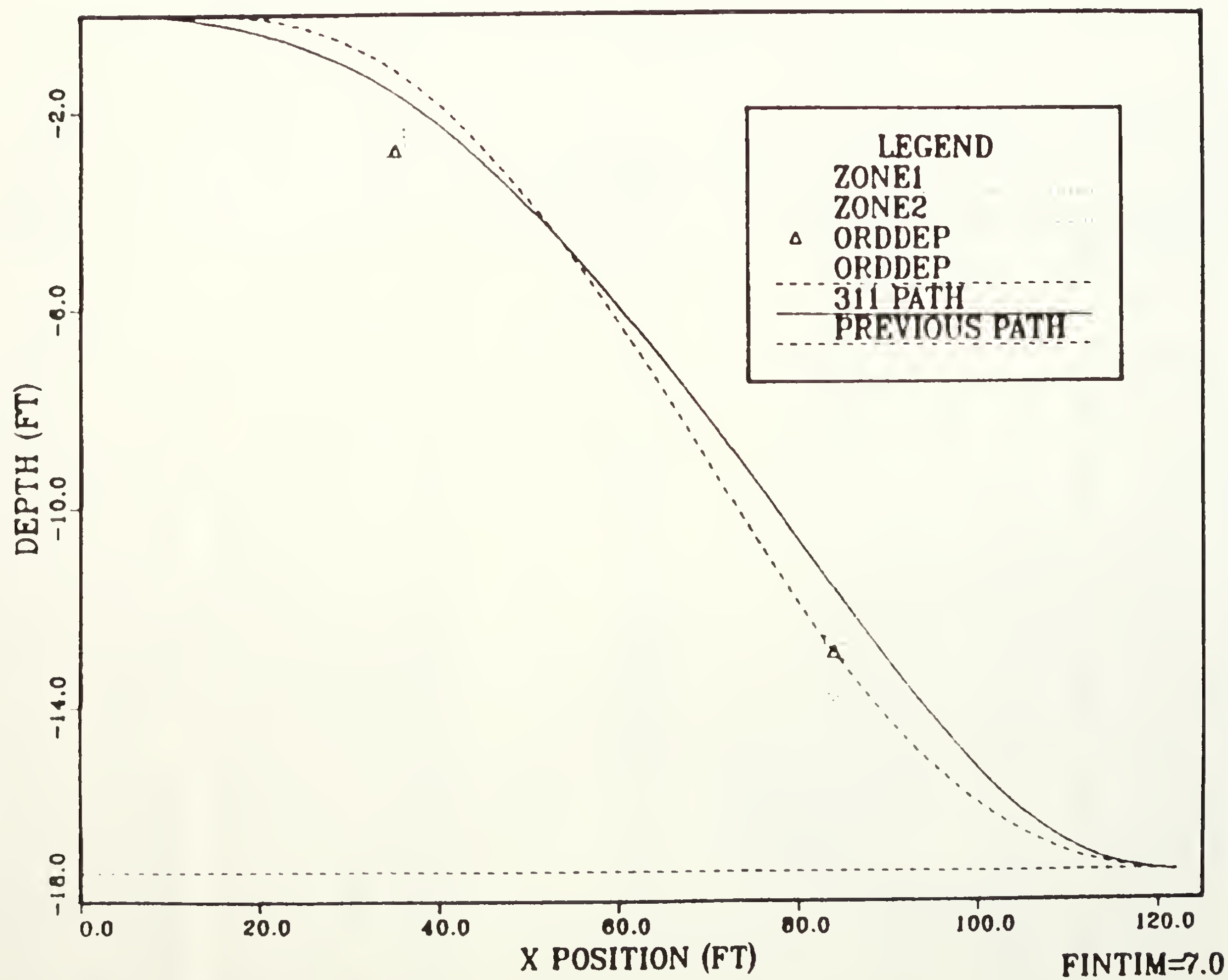

Figure 7.2 Two Obstacles Solution

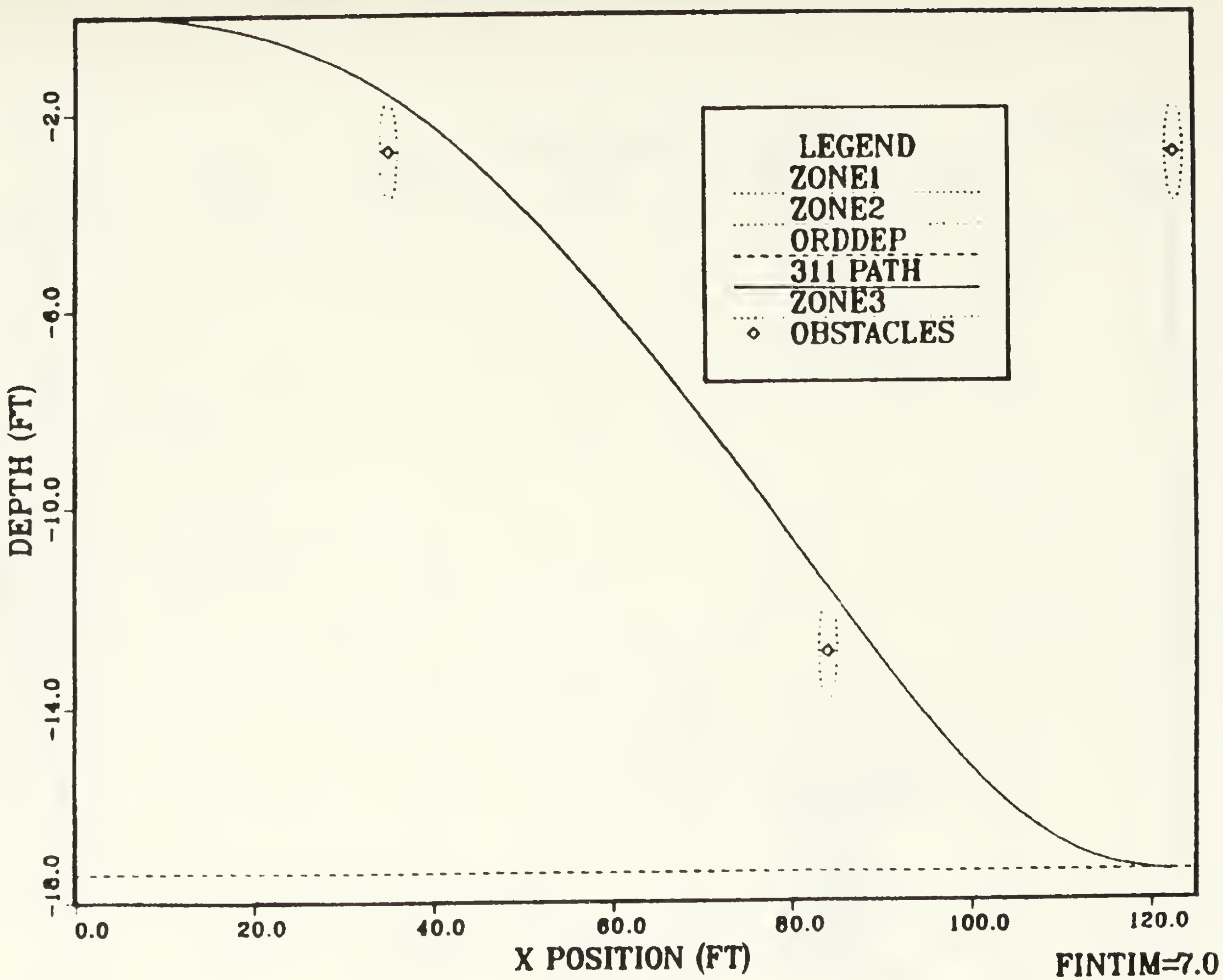

Figure 7.3 Three Obstacles Solution

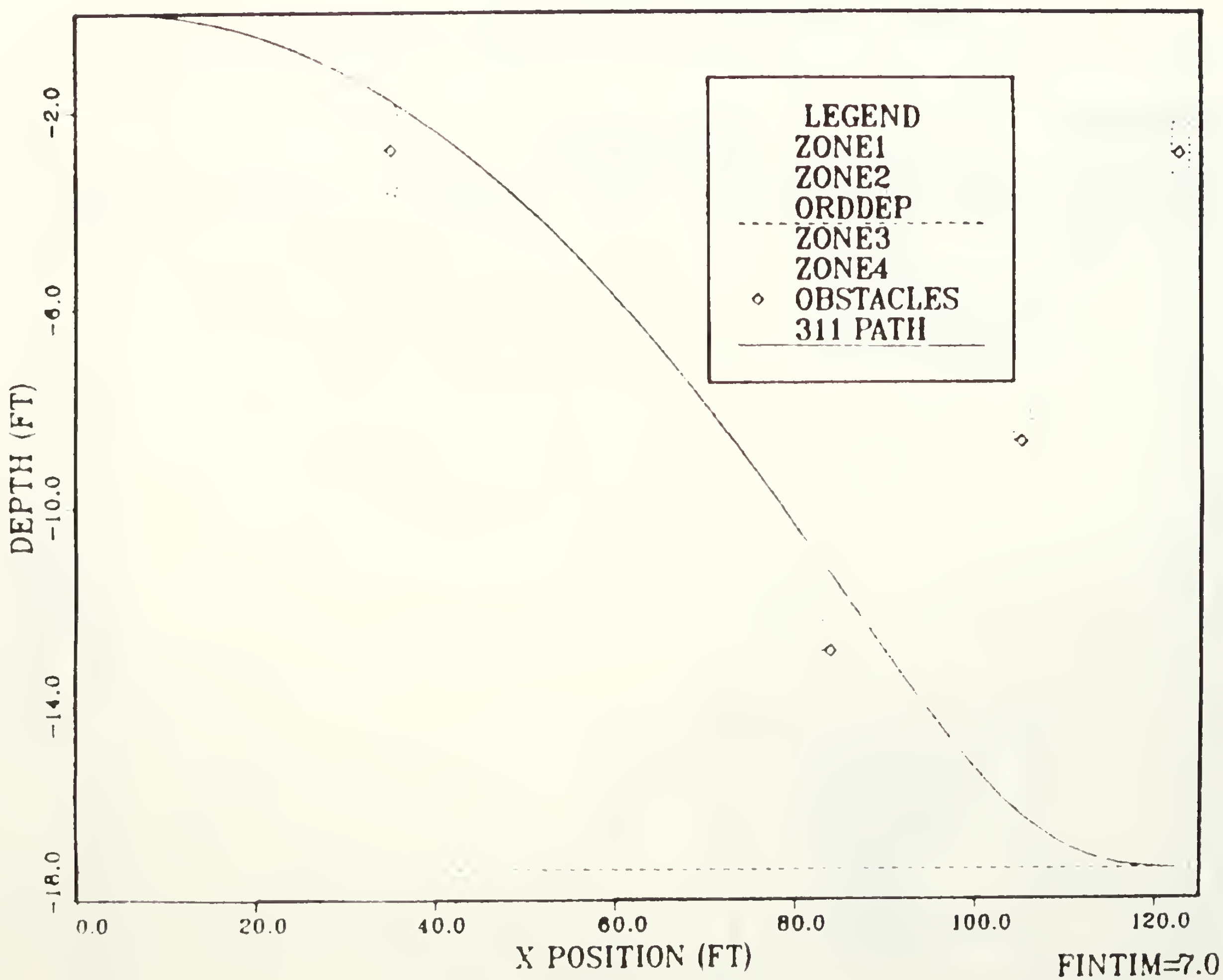

Figure 7.4 Four Obstacles Solution

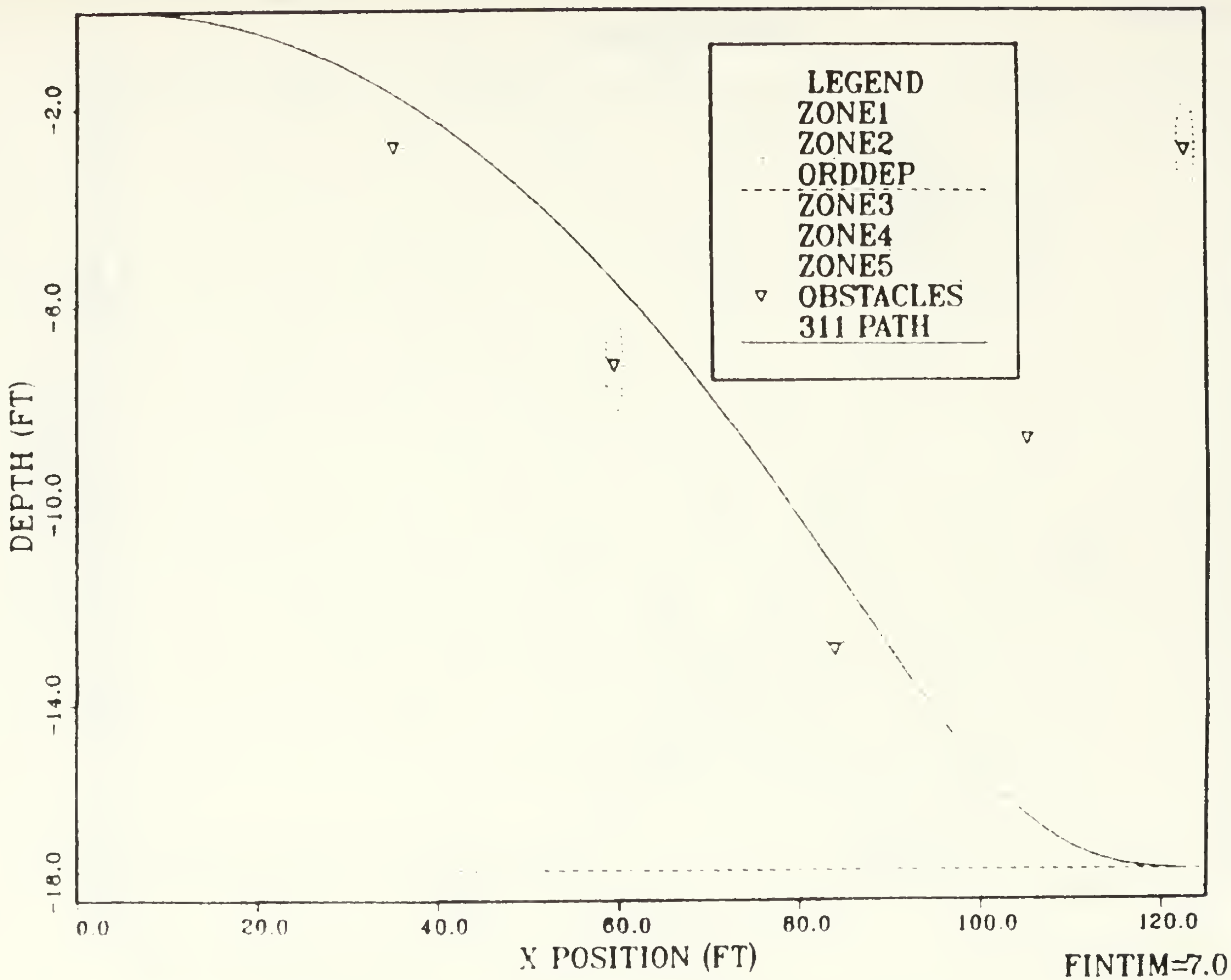

Figure 7.5 Five Obstacles Solution

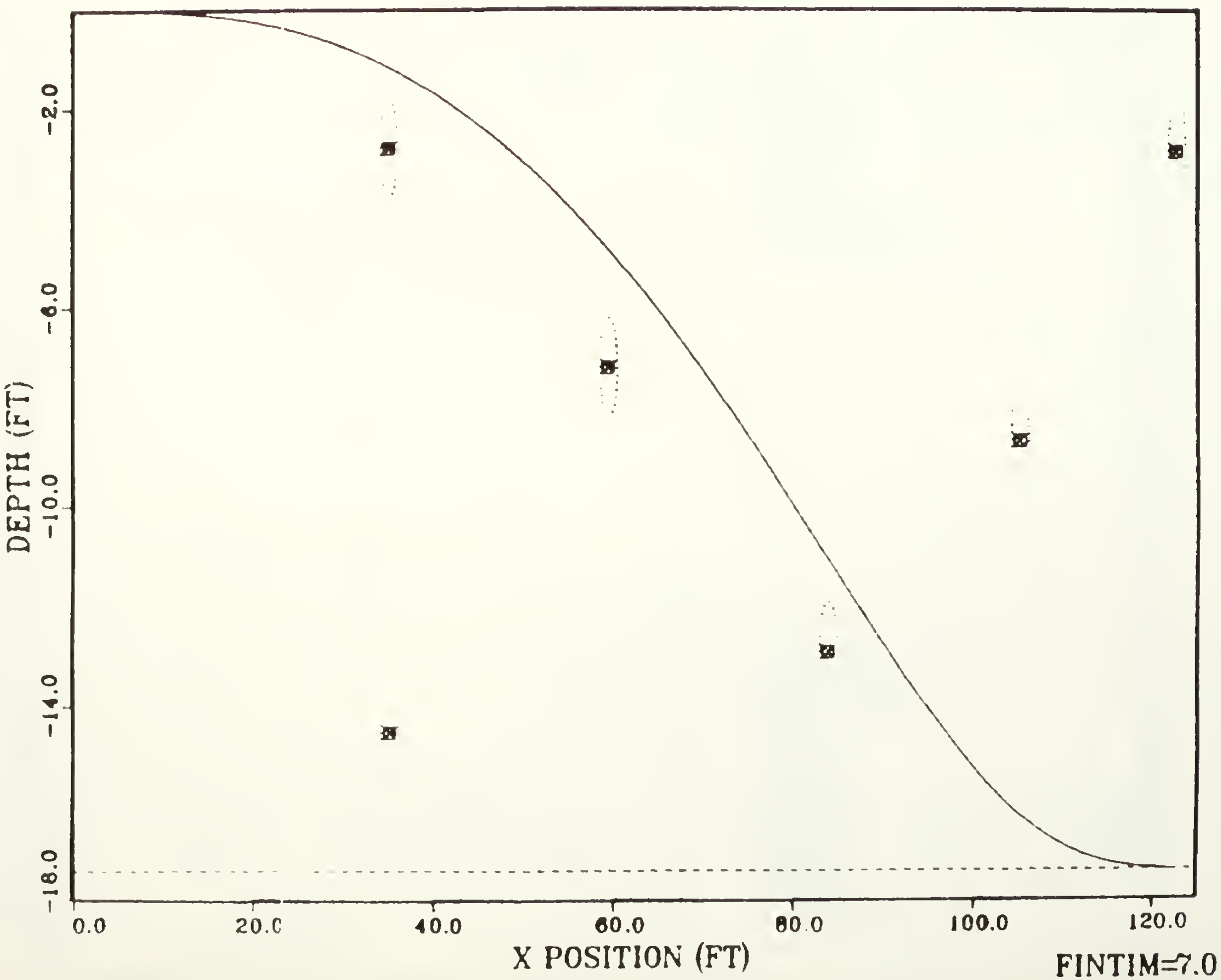

Figure 7.6 Six Obstacles Solution

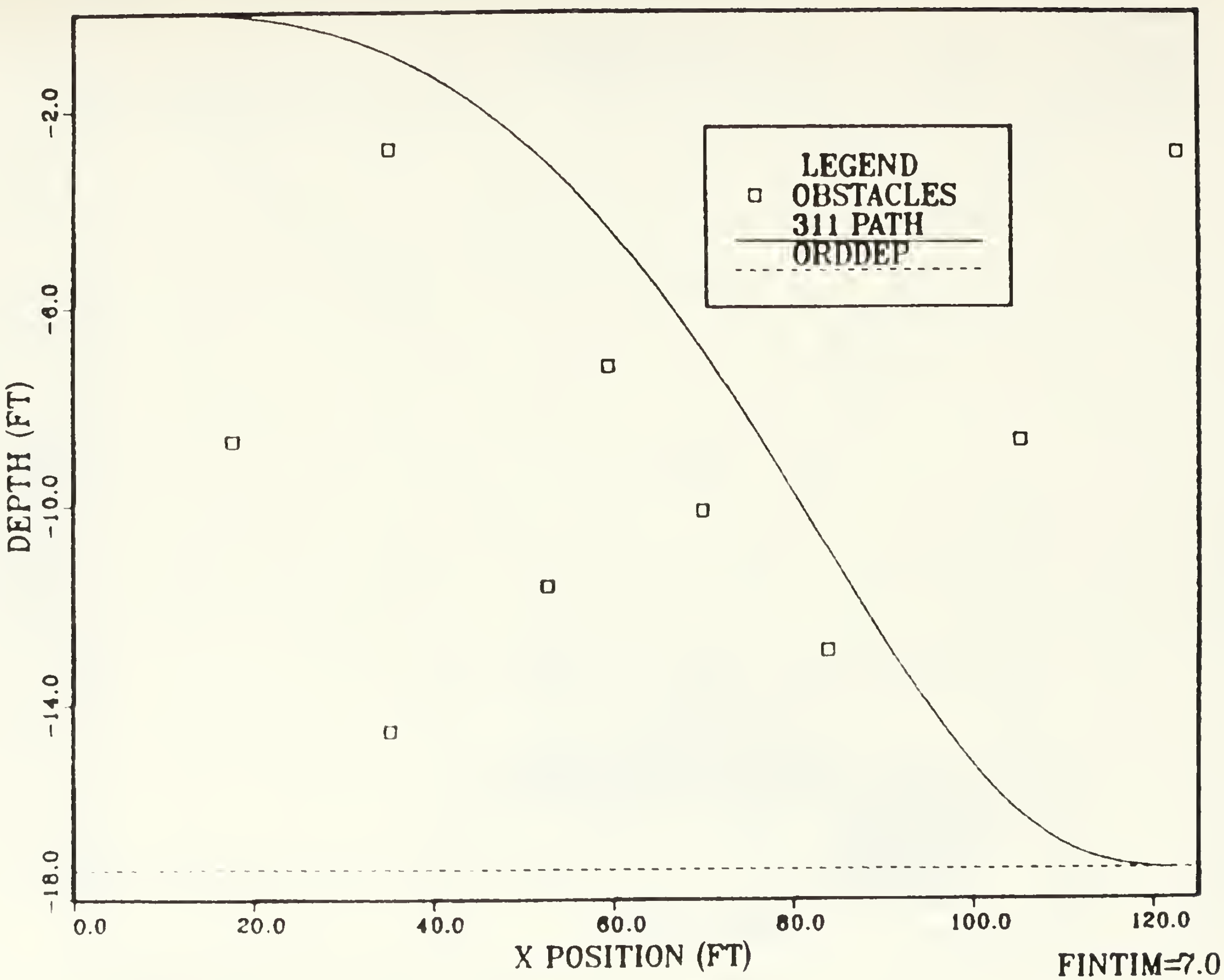

Figure 7.7 Nine Obstacles Solution

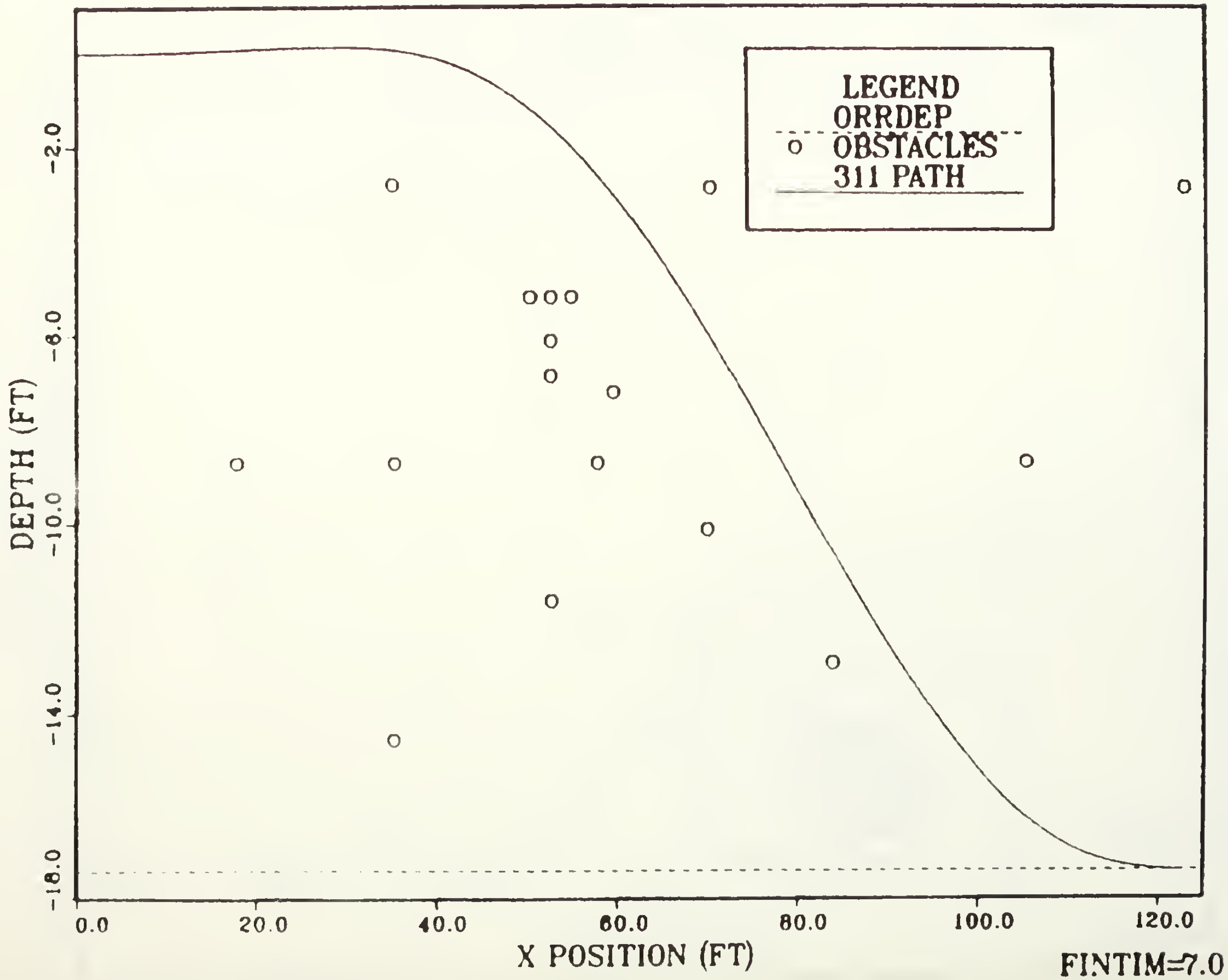

Figure 7.8 Seventeen Obstacles Solution

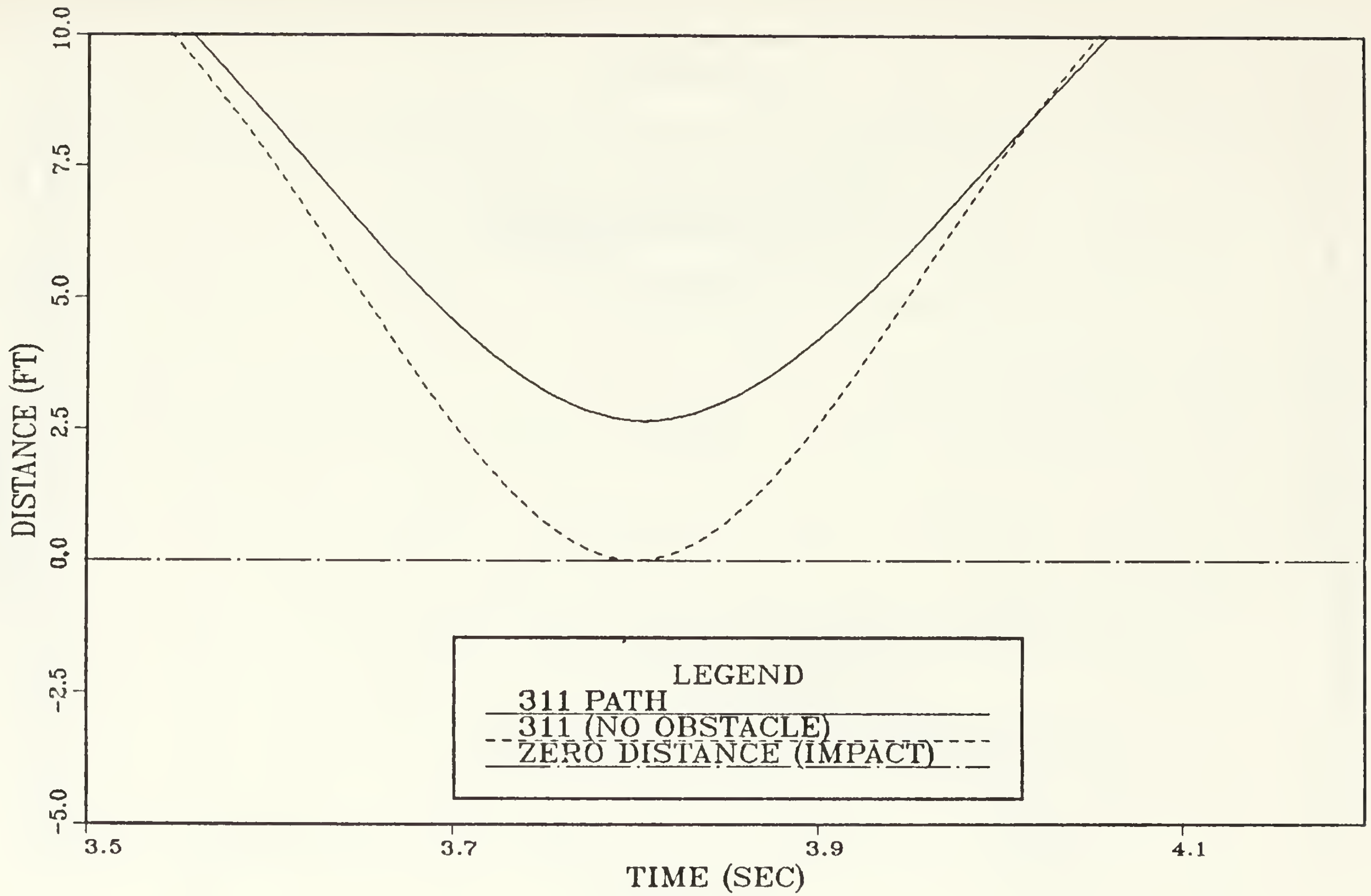

Figure 7.9 One Moving Obstacle Solution

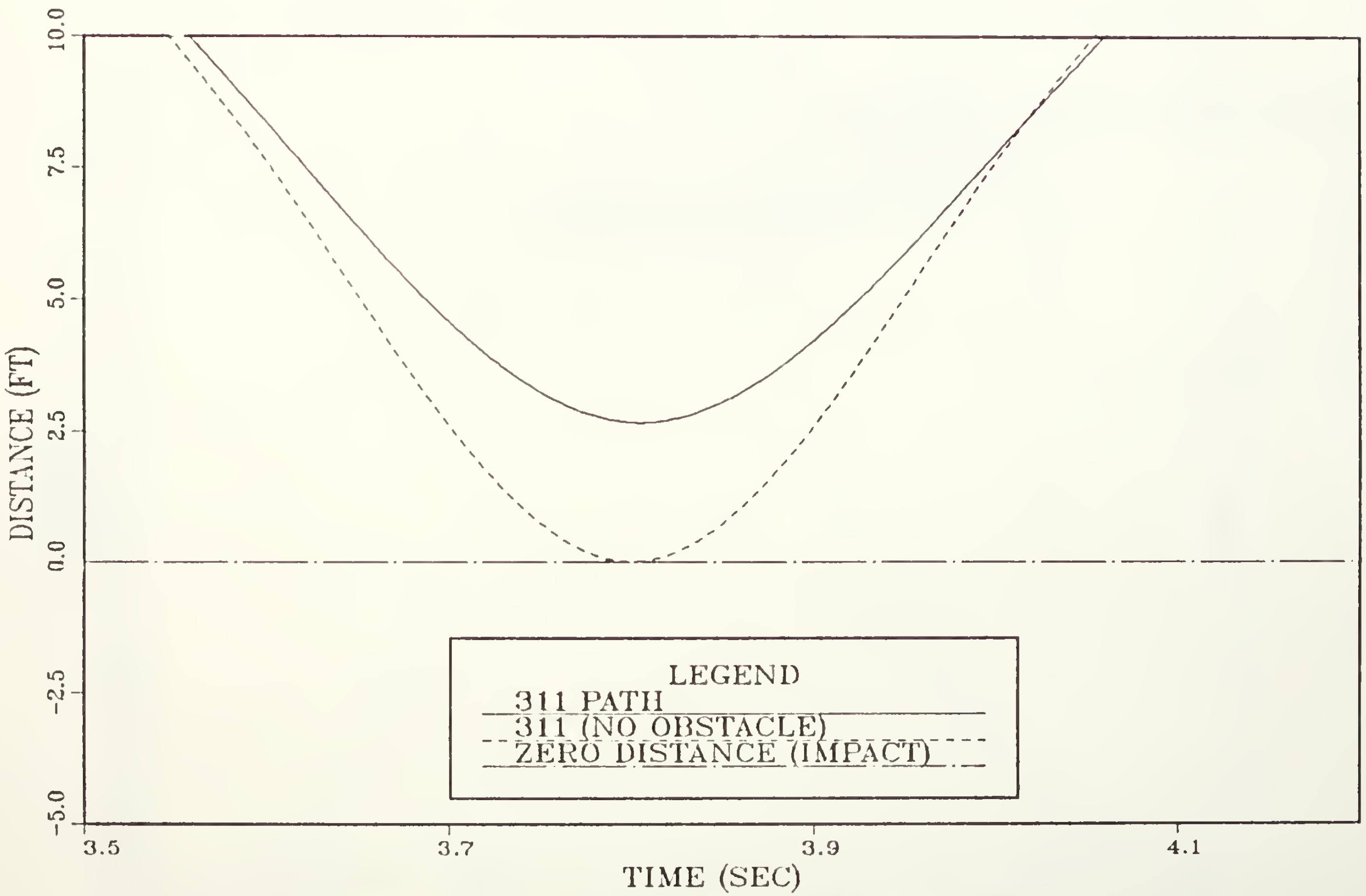

Figure 7.10 Two Moving Obstacles Solution (Obstacle 1)

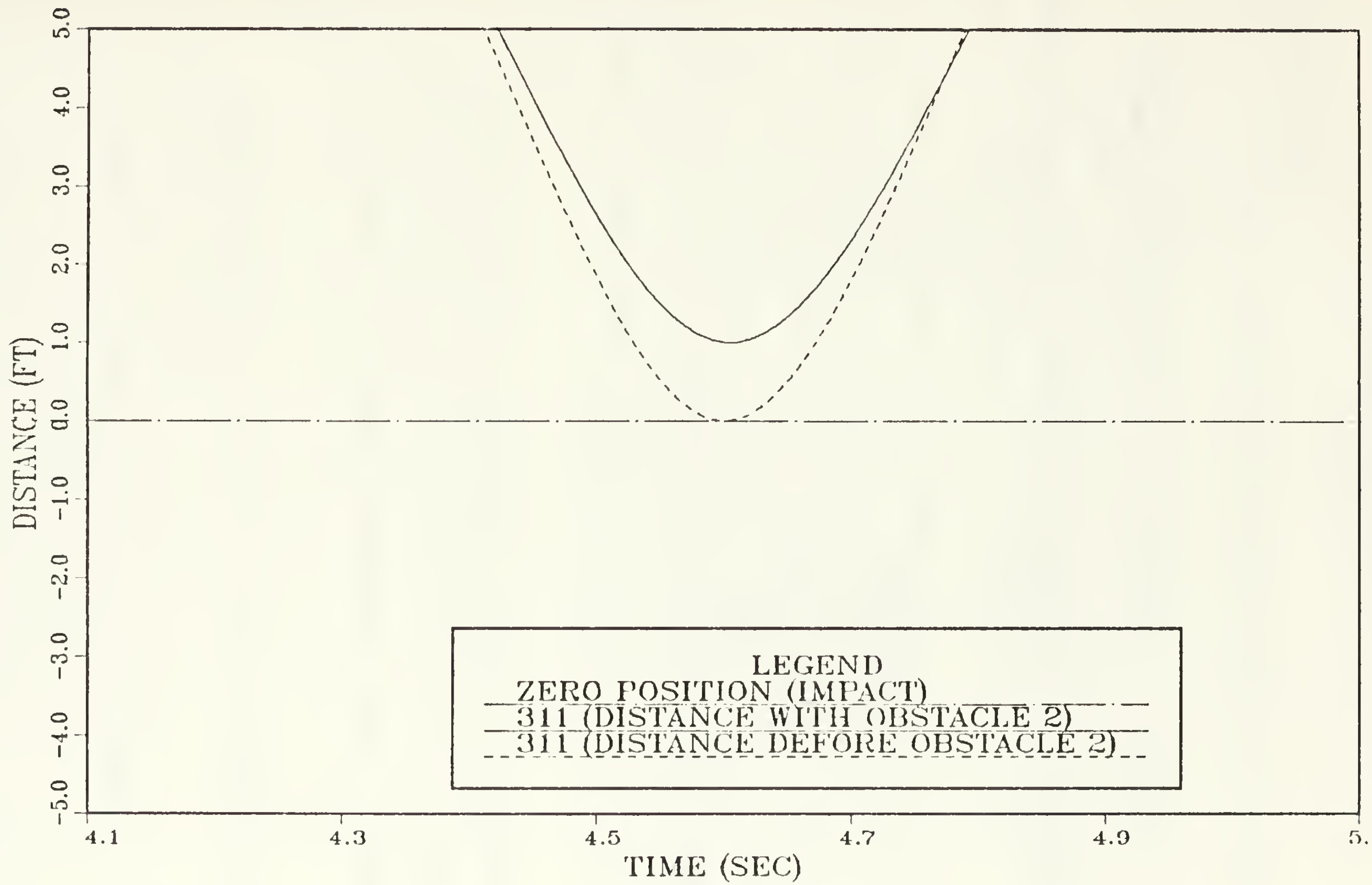

Figure 7.10 Two Moving Obstacles Solution (Obstacle 2)

TABLE 6. PROGRAM 311 COMPUTATIONAL COST-2D

NUMBER OF OBSTACLES	TIME (sec)
0	14.23
1 (moving)	23.88
2 (moving)	24.68
17 (fixed)	87.52

VIII. CONCLUSIONS AND RECOMMENDATIONS

A. CONCLUSIONS

The following conclusions can be drawn from this feasibility study:

1. Optimal control theory is a feasible method for determining obstacle avoidance paths in the presence of fixed and moving obstacles.

2. The introduction of obstacle constraints into the algorithm increases the computer computational costs.

3. The full linear model control inputs are not compatible with the full nonlinear model. When linear commands were placed in the nonlinear model, the vehicle's end condition was inconsistent with the desired end condition.

4. The best general algorithm for the two dimensional case was determined based on the ability of the algorithm to solve a variety of obstacle problems with a shortened FINTIM.

5. Scaling factors can be critical in achieving a desired problem solution.

6. In order to achieve a solution in three dimensions, it is necessary to increase the number of design variables for certain vehicle control inputs.

7. FINTIM is a critical variable whose value can change the solution to a specific problem.

B. RECOMMENDATIONS

1. Find a procedure to estimate the optimal scaling factors for end constraints.
2. Study the discretization factors in the three-dimensional case(s).
3. Study the selection of FINTIM in the two-dimensional case and in the three-dimensional case. Vehicle mission objectives should be considered in establishing guidelines.
4. Develop the optimization of the three-dimensional nonlinear model.
5. Develop the algorithm to include optimization of the propeller rpm control input.
6. Develop the program for efficient programming in a microprocessor.
7. Determine if the general algorithm recommended in this thesis is also applicable for three-dimensional obstacle avoidance cases.

APPENDIX

PROGRAMS

This appendix contains the four primary programs that were used for this feasibility study. They were:

1. OBST DSL - This is the state linear 2D model used for the 2D analysis.

2. TLO DSL - This is the ADSL program used to optimize the full scale linear model of bow plane, stern plane and rudder control vectors.

3. TNLO DSL - This is the ADSL program used to optimize the full scale nonlinear model for timing comparison studies.

4. TLNLO DSL - This is the ADSL program used to optimize the full scale linear model for bow plane, stern plane and rudder control inputs and with simulation of the full scale nonlinear model.

```
FILE: OBS      DSL      A1

TITLE  LINEAR AUV DYNAMIC PATH PLANNER FOR VERTICAL PLANE MOTION
* SEPARATED BOW AND STERN PLANE CONTROL NON-DIMENSIONAL
*
* 2D STATIONARY OBSTACLES
*
*
*
********************** ADSL SET UP ******************************
*
FIXED ISTRAT, IOPT, IONED, IPRINT, INFO, IGRAD, NDV, NCON
FIXED IDG, NGT, IC, NRA, NCOLA, NRWK, IWK, NRIWK, O
D     DIMENSION AW(42,42)
ARRAY WK(5000), IWK(500)
ARRAY DX(21), VLB(21), VUB(21), GW(05), DF(21), IDG(05), IC(05)
PARAM NRA=42, NCOLA=42, NRWK=5000, NRIWK=500
PARAM IGRAD=0, INFO=0, NDV=20, NCON=05, NGT=05
TABLE DX(1-2)=2*.0, DX(3-21)=19*0., IDG(1-4)=4*-1
TABLE VLB(1-9)=9*-.17452, VLB(11-19)=9*-.2443,VLB(10)=0.,VLB(20-21)=0.
TABLE VUB(1-9)=9*.17452, VUB(11-19)=9*.2443,VUB(10)=0.,VUB(20-21)=0.
TABLE IDG(5)=01*1
PARAM ISTRAT=3,IOPT=1, IONED=1, IPRINT=0000
INCON U=0.0
METHOD RECT
CONTROL FINTIM=7.0, DELT=.1
PRINT XPOS,ZPOS
*RINT DS,DB,DEPTH,PITCH,XPOS,ZPOS,DT
*
***************************DSL MODEL SET UP*************************
*
*
*      EQUILIBRIUM CONDITION IS CONSTANT SPEED (NON-DIMENSIONALIZED) BY
*              U0 = 6 FT/SEC
CONST  U0=1.0,A=10,B=11,C=12,D=13,E=14,F=15,G=16,H=17
*ONST XOBS1=36.0,ZOBS1=-12.0,XOBS2=72.5,ZOBS2=-5.82
*ONST XOBS3=90.0,ZOBS3=-16.,XOBS4=115.,ZOBS4=-17.
*****************************************************************

CONST  XOBS1=34.85,ZOBS1=-2.8297
CONST  XOBS2=83.64,ZOBS2=-12.960
CONST  XOBS3=122.5,ZOBS3=-2.90
CONST  XOBS4=105.0, ZOBS4=-8.74
CONST  XOBS5=59.245, ZOBS5=-7.2363
CONST  XOBS6=35.0,  ZOBS6=-14.58
CONST  XOBS7=17.5, ZOBS7=-8.74
CONST  XOBS8=52.5,ZOBS8=-11.66
CONST  XOBS9=69.7,ZOBS9=-10.155
CONST  XOBS10=70.0, ZOBS10=-2.9
CONST  XOBS11=52.275, ZOBS11=-6.1408
CONST  XOBS12=52.275,ZOBS12=-5.21
CONST  XOBS13=52.275, ZOBS13=-6.8836
CONST  XOBS14=50.0, ZOBS14=-5.21
CONST  XOBS15=54.55, ZOBS15=-5.21
CONST  XOBS16=57.5, ZOBS16=-8.74
CONST  XOBS17=35.0, ZOBS17=-8.74
*
*
```

```
CONST   UO=
*
CONST   MA=        , THETAO=   , ZO=   ,WO=   , IY=
*
CONST   ZW=       , ZQ=       , ZQDOT=          , ZWDOT=
CONST   ZDB=        , ZDS=         , ZO=
*
CONST   MW=        , MQ=         , MQDOT=         , MWDOT=
CONST   MDB=        , MDS=        , MTHETA=
*
INITIAL
      DSAVE1= SQRT((XPOS-XOBS1)*(XPOS-XOBS1)+(ZPOS-ZOBS1)*(ZPOS-ZOBS1))
      DSAVE2=SQRT((XPOS-XOBS2)*(XPOS-XOBS2)+(ZPOS-ZOBS2)*(ZPOS-ZOBS2))
      DSAVE3=SQRT((XPOS-XOBS3)*(XPOS-XOBS3)+(ZPOS-ZOBS3)*(ZPOS-ZOBS3))
      DSAVE4=SQRT((XPOS-XOBS4)*(XPOS-XOBS4)+(ZPOS-ZOBS4)*(ZPOS-ZOBS4))
      DSAVE5=SQRT((XPOS-XOBS5)*(XPOS-XOBS5)+(ZPOS-ZOBS5)*(ZPOS-ZOBS5))

      DSAVE6=SQRT((XPOS-XOBS6)*(XPOS-XOBS6)+(ZPOS-ZOBS6)*(ZPOS-ZOBS6))
      DSAVE7=SQRT((XPOS-XOBS7)*(XPOS-XOBS7)+(ZPOS-ZOBS7)*(ZPOS-ZOBS7))
      DSAVE8=SQRT((XPOS-XOBS8)*(XPOS-XOBS8)+(ZPOS-ZOBS8)*(ZPOS-ZOBS8))
      DSAVE9=SQRT((XPOS-XOBS9)*(XPOS-XOBS9)+(ZPOS-ZOBS9)*(ZPOS-ZOBS9))
      DSAVEA=SQRT((XPOS-XOBS10)*(XPOS-XOBS10)+...
      (ZPOS-ZOBS10)*(ZPOS-ZOBS10))
      DSAVEB=SQRT((XPOS-XOBS10)*(XPOS-XOBS10)+...
      (ZPOS-ZOBS10)*(ZPOS-ZOBS10))
      DSAVEC=SQRT((XPOS-XOBS10)*(XPOS-XOBS10)+...
      (ZPOS-ZOBS10)*(ZPOS-ZOBS10))
      DSAVED=SQRT((XPOS-XOBS10)*(XPOS-XOBS10)+...
      (ZPOS-ZOBS10)*(ZPOS-ZOBS10))
      DSAVEE=SQRT((XPOS-XOBS10)*(XPOS-XOBS10)+...
      (ZPOS-ZOBS10)*(ZPOS-ZOBS10))
      DSAVEF=SQRT((XPOS-XOBS10)*(XPOS-XOBS10)+...
      (ZPOS-ZOBS10)*(ZPOS-ZOBS10))
      DSAVEG=SQRT((XPOS-XOBS10)*(XPOS-XOBS10)+...
      (ZPOS-ZOBS10)*(ZPOS-ZOBS10))
      DSAVEH=SQRT((XPOS-XOBS10)*(XPOS-XOBS10)+...
      (ZPOS-ZOBS10)*(ZPOS-ZOBS10))
      ORDDEP = 1.0
      A1=-ZW
      A2=(MA-ZWDOT)
      A3=-(ZQ+MA)
      A4=-ZQDOT
      B1=-MW
      B2=-MWDOT
      B3=-MQ
      B4=(IY-MQDOT)
      B5=-MTHETA
      C1=ZDS
      C2=ZDB
      C3=MDS
      C4=MDB
      C5=C3-(B4*C1)/A4
      C6=C4-(B4*C2)/A4
      D1=B2-(B4*A2)/A4
      D2=B1-(B4*A1)/A4
      D3=B3-(B4*A3)/A4
      CALL DADS(INFO,ISTRAT,IOPT,IONED,IPRINT,IGRAD,NDV,NCON,DX,...
               VLB,VUB,OBJ,GW,IDG,NGT,IC,DF,AW,NRA,NCOLA,WK,NRWK,...
               IWK,NRIWK)
      IF(INFO.EQ.0) THEN
SAVE  THETDD,THETAD,THETA,W,Z,DEPTH,PITCH,DS,DB,BOWANG,STNANG
      ELSE
      ENDIF
      IF(INFO.EQ.0) DELPRT = 0.2
      IF(INFO.EQ.0) DELPLT = 0.2
DERIVATIVE
*
```

```
      THETDD=(1/A4)*(C1*DS+C2*DB-A1*W-A2*WDOT-A3*THETAD)
      WDOT= (1/D1)*(C5*DS + C6*DB - D2*W - D3*THETAD - B5*THETA)
      THETAD= INTGRL(THETAO,THETDD)
      THETA = INTGRL(THETAO,THETAD)
      W = INTGRL(WO,WDOT)
      Z = INTGRL(ZO,W-UO*THETA)
      DEPTH=-Z
      PITCH=THETA/.01745
      BOWANG=(DB/.01745)
      STNANG=(DS/.01745)
      INTGRD = ((W*W+(Z-ORDDEP)*(Z-ORDDEP)+...
               THETAD*THETAD+THETA*THETA)) + (DS*DS+DB*DB)
      OBJ1 = INTGRL(0.,(0.5)*INTGRD)
      OBJ = OBJ1
*
DYNAMIC
      RN=TIME/(FINTIM/10.-DELT/10000.)
      O=INT(RN)+1
      IF(O.EQ.11) O=10
*
* ADDITIONALLY THE PLANES SHOULD BE AT EQUILIBRIUM SO THE
* VEHICLE WILL PROCEED AT THIS NEW DEPTH WITHIN SOME TOLERANCE

*
      DS=DX(O)
      DB=DX(10+O)
      IF(O.GE.10) DS=0.
      IF(O.GE.10) DB=0.
*
*         CONSTRAINTS FOR A DIVE
*
*  ORDERED DEPTH = ORDDEP
      GW(1) =(Z-ORDDEP)/2.
      GW(2) =(ORDDEP-Z)/2.
*  AUV'S FINAL STATE MUST BE LEVEL FLIGHT AS FOLLOWS
      GW(3) = THETA *10.
      GW(4) = -THETA*10.
      GW(5)=-Z*100.
*
*   X-Z POSITIONING FOR OBSTACLE AVOIDANCE
*
      XPOS=17.425*TIME
      ZPOS=-Z*17.425
      DT=TIME*20./FINTIM
```

```
*
*   AVOIDING THE OBSTACLE
      DIST1=SQRT((XPOS-XOBS1)*(XPOS-XOBS1)+(ZPOS-ZOBS1)*(ZPOS-ZOBS1))
      DIST2=SQRT((XPOS-XOBS2)*(XPOS-XOBS2)+(ZPOS-ZOBS2)*(ZPOS-ZOBS2))
      DIST3=SQRT((XPOS-XOBS3)*(XPOS-XOBS3)+(ZPOS-ZOBS3)*(ZPOS-ZOBS3))
      DIST4=SQRT((XPOS-XOBS4)*(XPOS-XOBS4)+(ZPOS-ZOBS4)*(ZPOS-ZOBS4))
      DIST5=SQRT((XPOS-XOBS5)*(XPOS-XOBS5)+(ZPOS-ZOBS5)*(ZPOS-ZOBS5))
      DIST6=SQRT((XPOS-XOBS6)*(XPOS-XOBS6)+(ZPOS-ZOBS6)*(ZPOS-ZOBS6))
      DIST7=SQRT((XPOS-XOBS7)*(XPOS-XOBS7)+(ZPOS-ZOBS7)*(ZPOS-ZOBS7))
      DIST8=SQRT((XPOS-XOBS8)*(XPOS-XOBS8)+(ZPOS-ZOBS8)*(ZPOS-ZOBS8))
      DIST9=SQRT((XPOS-XOBS9)*(XPOS-XOBS9)+(ZPOS-ZOBS9)*(ZPOS-ZOBS9))
      DIST10=SQRT((XPOS-XOBS10)*(XPOS-XOBS10)+(ZPOS-ZOBS10)*...
      (ZPOS-ZOBS10))
      DIST11=SQRT((XPOS-XOBS11)*(XPOS-XOBS11)+(ZPOS-ZOBS11)*...
      (ZPOS-ZOBS11))
      DIST12=SQRT((XPOS-XOBS12)*(XPOS-XOBS12)+(ZPOS-ZOBS12)*...
      (ZPOS-ZOBS12))
      DIST13=SQRT((XPOS-XOBS13)*(XPOS-XOBS13)+(ZPOS-ZOBS13)*...
      (ZPOS-ZOBS13))
      DIST14=SQRT((XPOS-XOBS14)*(XPOS-XOBS14)+(ZPOS-ZOBS14)*...
      (ZPOS-ZOBS14))
      DIST15=SQRT((XPOS-XOBS15)*(XPOS-XOBS15)+(ZPOS-ZOBS15)*...
      (ZPOS-ZOBS15))
      DIST16=SQRT((XPOS-XOBS16)*(XPOS-XOBS16)+(ZPOS-ZOBS16)*...
      (ZPOS-ZOBS16))
      DIST17=SQRT((XPOS-XOBS17)*(XPOS-XOBS17)+(ZPOS-ZOBS17)*...
      (ZPOS-ZOBS17))
      IF(DIST1.LT.DSAVE1) DSAVE1=DIST1
      IF(DIST2.LT.DSAVE2) DSAVE2=DIST2
      IF(DIST3.LT.DSAVE3) DSAVE3=DIST3
      IF(DIST4.LT.DSAVE4) DSAVE4=DIST4
      IF(DIST5.LT.DSAVE5) DSAVE5=DIST5
      IF(DIST6.LT.DSAVE6) DSAVE6=DIST6
      IF(DIST7.LT.DSAVE7) DSAVE7=DIST7
      IF(DIST8.LT.DSAVE8) DSAVE8=DIST8
      IF(DIST9.LT.DSAVE9) DSAVE9=DIST9
      IF(DIST10.LT.DSAVEA) DSAVEA=DIST10
      IF(DIST11.LT.DSAVEB) DSAVEB=DIST11
      IF(DIST12.LT.DSAVEC) DSAVEC=DIST12
      IF(DIST13.LT.DSAVED) DSAVED=DIST13
      IF(DIST14.LT.DSAVEE) DSAVEE=DIST14
      IF(DIST15.LT.DSAVEF) DSAVEF=DIST15
      IF(DIST16.LT.DSAVEG) DSAVEG=DIST16
      IF(DIST17.LT.DSAVEH) DSAVEH=DIST17
      GW(6)=(9.-DSAVE1)
      GW(7)=(5.-DSAVE2)
      GW(8)=(3.-DSAVE3)
      GW(9)=(6.-DSAVE4)
      GW(10)=(1.-DSAVE5)
      GW(11)=(1.-DSAVE6)
      GW(12)=(1.-DSAVE7)
```

```
      GW(13)=(1.-DSAVE8)
      GW(14)=(1.-DSAVE9)
      GW(15)=(1.-DSAVEA)
      GW(16)=(1.-DSAVEB)
      GW(17)=(1.-DSAVEC)
      GW(18)=(1.-DSAVED)
      GW(19)=(1.-DSAVEE)
      GW(20)=(1.-DSAVEF)
      GW(21)=(1.-DSAVEG)
      GW(22)=(1.-DSAVEH)
TERMINAL

      IF(INFO.EQ.0) THEN
      PRINT*,DSAVE1,DSAVE2
      PRINT*,DSAVE3,DSAVE4
      PRINT*,DSAVE5,DSAVE6
      PRINT*,DSAVE7,DSAVE8
      PRINT*,DSAVE9,DSAVEA
      PRINT*,DSAVEB,DSAVEC
      PRINT*,DSAVED,DSAVEE
      PRINT*,DSAVEF,DSAVEG
      PRINT*,DSAVEH
      ELSE
      ENDIF
      IF(INFO.EQ.0) CALL ENDJOB
      CALL RERUN
*
END
STOP
```

```
FILE: TLO      DSL      A1

TITLE RUN:16-5  LINEAR AUV MODEL / STERN PLANE AND BOW PLANE SEPARATED
* (1) UPDATED:04/16/88
* (2) 100.00 FT DEPTH CHANGE IN 20 SEC
* (3) RIGHT OBJ EQUATION
* (4) ADS CONSTRAINTS ON DEPTH AND PITCH
* (5) OBSTACLE FURTHER DOWN THE TRAJECTORY AND ABOVE IT
* (6) CORRECT OBSTACLE AVOIDANCE ROUTINE ADDED
********************ADSL SET-UP***********************************
FIXED ISTRAT, IOPT, IONED, IPRINT, INFO, IGRAD, NDV, NCON
FIXED IDG, NGT, IC, NRA, NCOLA, NRWK, IWK, NRIWK, O, H,D,C,P
D      DIMENSION AW(42,42)
ARRAY WK(4000), IWK(1000)
ARRAY DX(40), VLB(40), VUB(40), GW(11), DF(41), IDG(11), IC(11)
PARAM NRA=42, NCOLA=42, NRWK=4000, NRIWK=1000
PARAM IGRAD=0, INFO=0, NDV=40, NCON=11, NGT=11
TABLE DX(1-2)=2*.0,DX(3-21)=19*0., IDG(1-10)=10*-1
TABLE DX(22-40)=19*0.
TABLE IDG(7-0)=1*1
TABLE VLB(1-9)=9*-.17452, VLB(11-19)=09*-.2443,VLB(10)=0.,VLB(20)=0.
TABLE VUB(1-9)=9*.17452, VUB(11-19)=9*.2443,VUB(10)=0.,VUB(20)=0.
TABLE VLB(21-39)=19*-.523627,VUB(21-39)=19*.523627,VUB(40-41)=0.
TABLE VLB(40-41)=0.
PARAM ISTRAT=3, IOPT=1, IONED=1, IPRINT=0000
INCON  H=0, OBS1=0.,YZONE=0.
METHOD RECT
CONTROL FINTIM=21. , DELT=.10
*RINT XPOSM,YPOSM,DEPTH,THETAM,PHIM,PSIM,DSM,DBM,DRM
PRINT XPOSM,YPOSM,DEPTH
*RINT DSM,DBM,DRM,PITCHM,XPOSM,YPOSM,DEPTH,NDT
*RINT THETAD,W,DEPTH,PITCH,XPOS,DEPTH,NDX,NDZ,NDT
*AVE  THETA,W,Z,DEPTH,PITCH,DS,DB,BOWANG,STNANG
*RAPH(DE=TEK618) TIME,DS
*RAPH(DE=TEK618) TIME,DEPTH
*RAPH(DE=TEK618) TIME,WDOT
*RAPH(DE=TEK618) TIME,W
*RAPH(DE=TEK618) TIME,THETDD
*RAPH(DE=TEK618) TIME,THETAD
*RAPH(DE=TEK618) TIME,THETA
*RAPH(DE=TEK618) TIME,PITCH
*RAPH(DE=TEK618) TIME,BOWANG
*RAPH(DE=TEK618) TIME,STNANG
******************D S L MODEL FOR LINEAR SIMULATION ******************
*                          LINEAR MODEL ONLY
D       COMMON/BLOCK1/ MMINV(6,6), MM(6,6), AA(12,12), BB(6,6)
D       COMMON/BLOCK2/ B(6,6),A(12,12), UMOD(6),GKK(6,21)
D       COMMON/BLOCK3/ F(12), FP(6), UCF(4)
D       COMMON/BLOCK4/ G4(4),GK4(4),BR(4),HH(4)
D       COMMON/BLOCK5/ XDOT(12),XDOTX(12), XDOTU(6)
FIXED  N,IA,IDGT,IER,LAST,J,K,M,JJ,KK,I
INTEGER
ARRAY  WKAREA(54), X(12)
*
*
CONST
*
*     LONGITUDINAL HYDRODYNAMIC COEFFICIENTS
*
CONST XPP = 7.03E-3  ,XQQ = -1.47E-2  ,XRR = 4.01E-3  ,XPR = 7.64E-4,...
      XUDOT=-7.58E-3 ,XWQ = -1.92E-1  ,XVP = -3.24E-3 ,XVR = 1.89E-2,...
      XQDS= 2.61E-2  ,XQDB= -2.6E-3   ,XRDR= -8.18E-4 ,XVV = 5.29E-2,...
      XWW = 1.71E-1  ,XVDR= 1.73E-3   ,XWDS= 4.6E-2   ,XWDB= 9.66E-3,...
      XDSDS=-1.16E-2 ,XDBDB=-8.07E-3  ,XDRDR=-1.01E-2 ,XQDSN=1.96E-3,...
      XWDSN=3.46E-3  ,XDSDSN=-1.62E-3
```

```
*
*      LATERAL HYDRODYNAMIC COEFFICIENTS
*
CONST YPDOT=1.27E-4  ,YRDOT=1.24E-3   ,YPQ = 4.125E-3 ,YQR =-6.51E-3,...
      YVDOT=-5.55E-2 ,YP  = 3.055E-3  ,YR = 2.97E-2   ,YVQ = 2.36E-2,...
      YWP = 2.35E-1  ,YWR = -1.88E-2  ,YV = -9.31E-2  ,YVW = 6.84E-2,...
      YDR = 2.73E-2  ,CDY = 3.5E-1
*
*      NORMAL HYDRODYNAMIC COEFFICIENTS


*
CONST ZQDOT=-6.81E-3 ,ZPP = 1.27E-4   ,ZPR = 6.67E-3  ,ZRR =-7.35E-3,...
      ZWDOT=-2.43E-1 ,ZQ = -1.35E-1   ,ZVP = -4.81E-2 ,ZVR = 4.55E-2,...
      ZW = -3.02E-1  ,ZVV = -6.84E-2  ,ZDS = -7.255E-2,ZDB =-2.58E-2,...
      ZQN = -2.88E-3 ,ZWN = -5.07E-3  ,ZDSN= -1.015E-2,CDZ = 1.0
*
*      ROLL HYDRODYNAMIC COEFFITIENTS
*
CONST KPDOT=-1.01E-3 , KRDOT=-3.37E-5 ,KPQ = -6.93E-5 ,KQR = 1.68E-2,...
      KVDOT=1.27E-4  , KP = -1.1E-2   ,KR = -8.41E-4  ,KVQ=-5.115E-3,...
      KWP = -1.27E-4 , KWR = 1.39E-2  ,KV = 3.055E-3  ,KVW =-1.87E-1,...
      KPN = -5.73E-4, KDB = 6.94E-3
*
*      PITCH HYDRODYNAMIC COEFFICIENTS
*
CONST MQDOT= -1.68E-2, MPP = 5.26E-5  ,MPR = 5.04E-3  ,MRR =-2.86E-2,...
      MWDOT= -6.81E-3, MQ = -6.86E-2  ,MVP = 1.18E-3  ,MVR = 1.73E-2,...
      MW = 9.86E-2   , MVV = -2.51E-2 ,MDS = -4.12E-2 ,MDB = 6.94E-3,...
      MQN = -1.64E-3 , MWN = -2.88E-3 ,MDSN = -5.76E-3
*
*      YAW HYDRODYNAMIC COEFFICIENTS
*
CONST NPDOT=-3.37E-5 , NRDOT=-3.4E-3  ,NPQ = -2.11E-2 ,NQR = 2.75E-3,...
      NVDOT=1.24E-3  , NP = -8.405E-4 ,NR = -1.64E-2  ,NVQ =-9.99E-3,...
      NWP = -1.75E-2 , NWR = 7.35E-3  ,NV = -7.42E-3  ,NVW =-2.67E-2,...
      NDR = -1.29E-2
*
*      MASS CHARACTERISTICS OF THE FLOODED MARK IX VEHICLE
*
CONST WEIGHT = 15900 , BOY = 15900    ,VOL = 248.44   ,XG =-0.1     ,...
      YG = 0.0       , ZG = 0.061     ,XB =-0.1       ,ZB =0.023    ,...
      IX = 1760      , IY = 9450      ,IZ = 10700     ,IXZ = -6.65  ,...
      IYZ = - 7.0    , IXY = - 7.0    ,YB = 0.0                     ,...
      L = 17.425     , RHO = 1.94     ,G = 32.2       ,NU = 1.5E-5  ,...
      A0 = 1.57      ,KPROP = 0.0     ,NPROP = 0.0,    X1TEST=0.01  ,...
      DEGRUD= 10.0    ,DEGSTN=  0.0
*
CONST  XOBS1=36.0
CONST  ZOBS1= -12.0
```

```
*      INPUT INITIAL CONDITIONS HERE IF REQUIRED
*
INITIAL
*
*      DSAVE1=SQRT((XPOSM-XOBS1)*(XPOSM-XOBS1)+...
*            (ZPOSM-ZOBS1)*(ZPOSM-ZOBS1))
*      INITIALIZE ALL MATRICES AND ARRAYS TO ZERO
NOSORT
       ORDDEP=20.
       YORD= 40.
       D=0
       H=H+1
       IF (H.EQ.1) THEN
       N = 6
       DO 2  J = 1,N
          JJ= J+N
          DO  1 K = 1,N
          KK= K+N
          KKK= KK + N
          MMINV(J,K) = 0.0
          X(J) = 0.0
          X(JJ) = 0.0
          XDOT(J) = 0.0
          XDOT(JJ) = 0.0
          XDOTX(J) = 0.0
          XDOTX(JJ) = 0.0
          XDOTU(J) = 0.0
          UMOD(J) = 0.0
          MM(J,K) = 0.0
          BB(J,K) = 0.0
          B(J,K) = 0.0

          AA(J,K)= 0.0
          AA(JJ,KK)= 0.0
          AA(J,KK)= 0.0
          AA(JJ,K)= 0.0
          A(J,KK)= 0.0
          A(JJ,K) = 0.0
          A(J,K) = 0.0
          A(JJ,KK)= 0.0
          GKK(J,K)= 0.0
          GKK(J,KK)=0.0
          GKK(J,KKK)=0.0
1         CONTINUE
2      CONTINUE
*
*      INPUT THE LINEARIZATION POINT PARAMETERS
*
       U0 =6.0
       V0 = 0.0
       W0 = 0.0
       P0 = 0.0
       Q0 = 0.0
       R0 = 0.0
       PHI0 = 0.0
       THETA0 = 0.0
       PSI0 = 0.0
       SUM = 0.0
       JFLAG = 0
       IFLAG = 0
       KFLAG = 0
*
```

```
*       INPUT THE MODEL STATES INITIAL CONDITIONS
*
        UM = 6.0
        VM = 0.0
        WM = 0.0
        PM = 0.0
        QM = 0.0
        RM = 0.0
        XPOSM = 0.0
        YPOSM = 0.0
        ZPOSM = 0.0
        PHIM = 0.0
        THETAM = 0.0
        PSIM = 0.0
*
*
*       INPUT THE VEHICLE INITIAL CONDITIONS
*
*
*       INITIALIZE THE CONTROLS
*
        DBOY= 0.0
        DR=0.0
        DS= 0.00000
*       DSM=0.
*       DBM=0.
        DB=0.000000
        DRM=0.0
        DRPM=0.
        RPM = 500.00
        LATYAW = 0.0
        NORPIT = 0.0
*
*
        MASS = WEIGHT/G
*
        DIVAMP = DEGSTN*0.0174532925
        RUDAMP = DEGRUD*0.0174532925
*
*       THE LINEAR PROPULSION MODEL
*
*


*       ETA = 0.012*RPM/U0
        ETA = 1.0
        RE = U0*L/NU
        CD0 =  .00385 + (1.296E-17)*(RE - 1.2E7)**2
        CT  = 0.008*L**2*ETA*ABS(ETA)/(A0)
        CT1 = 0.008*L**2/(A0)
        EPS = -1.0+(SQRT(CT+1.0)-1.0)/(SQRT(CT1+1.0)-1.0)
        XPROP = CD0*(ETA*ABS(ETA) - 1.0)

*       N=6
*       DO 15 J = 1,N
*          DO 10 K =1,N
*          MMINV(J,K)=0.0
*          MM(J,K) = 0.0
*0         CONTINUE
*5       CONTINUE
*
*       CALCULATE THE MASS MATRIX
*
        MM(1,1) = MASS -((RHO/2)*(L**3)*XUDOT)
        MM(1,5) = MASS*ZG
        MM(1,6) = -MASS*YG
```

```
      MM(2,2) = MASS -((RHO/2)*(L**3)*YVDOT)
      MM(2,4) = -MASS*ZG -((RHO/2)*(L**4)*YPDOT)
      MM(2,6) = MASS*XG - ((RHO/2)*(L**4)*YRDOT)

      MM(3,3) = MASS - ((RHO/2)*(L**3)*ZWDOT)
      MM(3,4) = MASS*YG
      MM(3,5) = -MASS*XG -((RHO/2)*(L**4)*ZQDOT)

      MM(4,2) = -MASS*ZG - ((RHO/2)*(L**4)*KVDOT)
      MM(4,3) = MASS*YG
      MM(4,4) = IX - ((RHO/2)*(L**5)*KPDOT)
      MM(4,5) = -IXY
      MM(4,6) = -IXZ -((RHO/2)*(L**5)*KRDOT)

      MM(5,1) = MASS*ZG
      MM(5,3) = -MASS*XG -((RHO/2)*(L**4)*MWDOT)
      MM(5,4) = -IXY
      MM(5,5) = IY -((RHO/2)*(L**5)*MQDOT)
      MM(5,6) = -IYZ

      MM(6,1) = -MASS*YG
      MM(6,2) = MASS*XG -((RHO/2)*(L**4)*NVDOT)
      MM(6,4) = -IXZ - ((RHO/2)*(L**5)*NPDOT)
      MM(6,5) = -IYZ
      MM(6,6) = IZ - ((RHO/2)*(L**5)*NRDOT)
*
*
      LAST = N*N+3*N
      DO 20 M = 1,LAST
      WKAREA(M) = 0.0
20    CONTINUE
*
      IER = 0
      IA = 6
      IDGT = 4
*
      CALL LINV2F(MM,N,IA,MMINV,IDGT,WKAREA,IER)
*
*    CALCULATE THE A MATRIX FOR THE LINEAR MODEL
*
*
*
      A(1,1) = RHO/2*L**3*(XQDS*DS*Q0+XQDB/2*DB*Q0+XRDR*R0*DR)+...
               RHO/2*L**2*(XVDR*V0*DR+XWDS*DS*W0+XWDB/2*DB*W0 + ...
               2*U0*(XDSDS*DS**2 + XDBDB/2*DB**2 + XDRDR*DR**2))+ ...
               RHO/2*L**3*XQDSN*Q0*DS*EPS+RHO/2*L**2*(XWDSN*W0*DS+...
               2*XDSDSN*U0*DS**2)*EPS+RHO*L**2*U0*XPROP+RHO/2*L**3*...
               XQDB/2*DB*Q0+RHO/2*L**2*XWDB/2*DB*W0+RHO*L**2*U0*...
               XDBDB/2*DB**2
```

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```
      A(1,2) = MASS*R0+RHO/2*L**3*(XVP*P0+ XVR*R0) + RHO/2*L**2* ...
               (2*XVV*V0 + XVDR*U0*DR)
      A(1,3) = -MASS*Q0 + RHO/2*L**3*(XWQ*Q0)+RHO/2*L**2*(2*XWW*W0+...
               XWDS*DS*U0+(XWDB/2*DB+XWDB/2*DB)*U0 +XWDSN*U0*DS*EPS)
      A(1,4) = -MASS*YG*Q0-MASS*ZG*R0+ RHO/2*L**4*(2*XPP*P0+XPR*R0)...
               + RHO/2*L**3*(XVP*V0)
      A(1,5) = -MASS*W0+2*MASS*XG*Q0 -MASS*YG*P0+RHO/2*L**4*2*XQQ*Q0...
               +RHO/2*L**3*(XWQ*W0+XQDS*DS*U0+XQDB/2*DB*U0)+RHO/2* ...
               L**3*XQDSN*U0*DS*EPS+RHO/2*L**3*XQDB/2*DB*U0
      A(1,6) = MASS*V0+2*MASS*XG*R0-MASS*ZG*P0+RHO/2*L**4*(2*XRR*R0...
               + XPR*P0) + RHO/2*L**3*(XVR*V0 + XRDR*U0*DR)
      A(1,11)= -(WEIGHT - BOY)*COS(THETA0)
*
      A(2,1) = -MASS*R0+RHO/2*L**3*(YP*P0+YR*R0)+RHO/2*L**2*(YV*V0+...
               2*YDR*U0*DR)
      A(2,2) = RHO/2*L**3*YVQ*Q0+RHO/2*L**2*(YV*U0+YVW*W0)
      A(2,3) = MASS*P0+ RHO/2*L**3*(YWP*P0+YWR*R0)+RHO/2*L**2*YVW*V0
      A(2,4) = MASS*W0-MASS*XG*Q0+2*MASS*YG*P0+RHO/2*L**4*YPQ*Q0+...
               RHO/2*L**3*(YP*U0+ YWP*W0)
      A(2,5) = -MASS*XG*P0-MASS*ZG*R0+RHO/2*L**4*(YPQ*P0+YQR*R0) +...
               RHO/2*L**3*YVQ*V0
      A(2,6) = -MASS*U0+2*MASS*YG*R0-MASS*ZG*Q0+RHO/2*L**4*YQR*Q0 +...
               RHO/2*L**3*(YR*U0 + YWR*W0)
      A(2,10)= (WEIGHT - BOY)*COS(THETA0)*COS(PHI0)
      A(2,11)= -(WEIGHT - BOY)*SIN(THETA0)*SIN(PHI0)
*
      A(3,1) = MASS*Q0+RHO/2*L**3*ZQ*Q0+RHO/2*L**2*(ZW*W0+2*U0*ZDS*DS...
               +2*U0*ZDB/2*DB+(ZWN*W0+2*ZDSN*U0*DS)*EPS)+RHO/2*L**3*...
               ZQN*Q0*EPS+ RHO/2*L**2*2*U0*ZDB/2*DB
      A(3,2) = -MASS*P0+RHO/2*L**3*(ZVP*P0+ZVR*R0)+RHO/2*L**2*2*ZVV*V0
      A(3,3) = RHO/2*L**2*(ZW*U0 + ZWN*U0*EPS)
      A(3,4) = -MASS*V0-MASS*XG*R0+2*MASS*ZG*P0+ RHO/2*L**4*(2*ZPP*...
               P0 + ZPR*R0) + RHO/2*L**3*ZVP*V0
      A(3,5) = MASS*U0 - MASS*YG*R0+2*MASS*ZG*Q0+RHO/2*L**3*ZQ*U0 +...
               RHO/2*L**3*ZQN*U0*EPS
      A(3,6) =-MASS*XG*P0-MASS*YG*Q0+RHO/2*L**4*(ZPR*P0+2*ZRR*R0)+...
               RHO/2*L**3*ZVR*V0
      A(3,10)= -(WEIGHT - BOY)*COS(THETA0)*SIN(PHI0)
      A(3,11)= -(WEIGHT - BOY)*SIN(THETA0)*COS(PHI0)
*
      A(4,1) = MASS*YG*Q0 + MASS*ZG*R0 + RHO/2*L**4*(KP*P0 + ...
               KR*R0)+RHO/2*L**3*(KV*V0+2*U0*(KDB/2*DB-KDB/2*DB))+...
               RHO/2*L**3*U0*KPROP+ RHO/2*L**4*KPN*P0*EPS
      A(4,2) = -MASS*YG*P0 + RHO/2*L**4*KVQ*Q0 + RHO/2*L**2*(KV*U0...
               + KVW*W0)
      A(4,3) = -MASS*ZG*P0 + RHO/2*L**4*(KWP*P0 + KWR*R0) + ...
               RHO/2*L**3*KVW*V0
      A(4,4) = -IXY*R0 + IXZ*Q0 - MASS*YG*V0 - MASS*ZG*W0 + ...
               RHO/2*L**5*KPQ*Q0 + RHO/2*L**4*(KP*U0+KWP*W0)
      A(4,5) = -IZ*R0 + IY*R0 + 2*IYZ*Q0 + IXZ*P0 + MASS*YG*U0 +...
               RHO/2*L**5*(KPQ*P0 + KQR*R0) + RHO/2*L**4*KVQ*V0
      A(4,6) = -IZ*Q0 + IY*Q0 - 2*IYZ*R0 + MASS*ZG*U0 + ...
               RHO/2*L**5*KQR*Q0 + RHO/2*L**4*(KR*U0+KWR*W0)
      A(4,10)= -(YG*WEIGHT-YB*BOY)*COS(THETA0)*SIN(PHI0)...
               -(ZG*WEIGHT-ZB*BOY)*COS(THETA0)*COS(PHI0)
      A(4,11)= -(YG*WEIGHT-YB*BOY)*SIN(THETA0)*COS(PHI0)...
               +(ZG*WEIGHT-ZB*BOY)*SIN(THETA0)*SIN(PHI0)
*
```

```
A(5,1) = -MASS*XG*Q0 + RHO/2*L**4*MQ*Q0 + RHO/2*L**3*MW*W0 +...
         RHO/2*L**3*U0*(MDS*DS+MDB/2*DB) + RHO/2*L**4*MQN*Q0*...
         EPS + RHO/2*L**3*(MWN*W0 + 2*MDSN*U0*DS)*EPS+...
         RHO/2*L**3*U0*MDB/2*DB
A(5,2) = MASS*XG*P0 + MASS*ZG*R0 + RHO/2*L**4*(MVP*P0 + ...
         MVR*R0) + RHO*L**3*MVV*V0
A(5,3) = -MASS*ZG*Q0 + RHO/2*L**3*MW*U0 + RHO/2*L**3*MWN*U0*EPS
A(5,4) = -IX*R0 + IZ*R0 - IYZ*Q0 - 2*IXZ*P0 + MASS*XG*V0 + ...
         RHO/2*L**5*(2*MPP*P0 + MPR*R0) + RHO/2*L**4*MVP*V0
A(5,5) = IXY*R0 -IYZ*P0 - MASS*XG*U0 -MASS*ZG*W0 + RHO/2*...
         L**4*MQ*U0 + RHO/2*L**4*MQN*U0*EPS
A(5,6) = -IX*P0 + IZ*P0 + IXY*Q0 + 2*IXZ*R0 + MASS*ZG*V0 +...
         RHO/2*L**5*(MPR*P0+2*MRR*R0)+RHO/2*L**4*MVR*V0
A(5,10)= (XG*WEIGHT-XB*BOY)*COS(THETA0)*SIN(PHI0)


A(5,11)= (XG*WEIGHT-XB*BOY)*SIN(THETA0)*COS(PHI0) - ...
         (ZG*WEIGHT-ZB*BOY)*COS(THETA0)
*
A(6,1) = -MASS*XG*R0 + RHO/2*L**4*(NP*P0 +NR*R0) + RHO/2*...
         L**3*(NV*V0+2*NDR*U0*DR)+RHO*L**3*U0*NPROP
A(6,2) = -MASS*YG*R0 + RHO/2*L**4*NVQ*Q0 + RHO/2*L**3*(NV*U0+...
         NVW*W0)
A(6,3) = MASS*XG*P0 + MASS*YG*Q0 + RHO/2*L**4*(NWP*P0+NWR*R0)+...
         RHO/2*L**3*NVW*V0
A(6,4) = -IY*Q0 + IX*Q0 + 2*IXY*P0 +IYZ*R0 + MASS*XG*W0+...
         RHO/2*L**5*NPQ*Q0 + RHO/2*L**4*(NP*U0+NWP*W0)
A(6,5) = -IY*P0 + IX*P0 - 2*IXY*Q0 - IXZ*R0 + MASS*YG*W0+...
         RHO/2*L**5*(NPQ*P0+NQR*R0) + RHO/2*L**4*NVQ*V0
A(6,6) = IYZ*P0 -IXZ*Q0 - MASS*XG*U0 -MASS*YG*V0 + ...
         RHO/2*L**5*NQR*Q0 + RHO/2*L**4*(NR*U0 +NWR*W0)
A(6,10)= (XG*WEIGHT-XB*BOY)*COS(THETA0)*COS(PHI0)
A(6,11)= -(XG*WEIGHT-XB*BOY)*SIN(THETA0)*SIN(PHI0) +...
         (YG*WEIGHT-YB*BOY)*COS(THETA0)
*
A(7,1) = COS(PSI0)*COS(THETA0)
A(7,2) = COS(PSI0)*SIN(THETA0)*SIN(PHI0) - SIN(PSI0)*COS(PHI0)
A(7,3) = COS(PSI0)*SIN(THETA0)*COS(PHI0) + SIN(PSI0)*SIN(PHI0)
A(7,10)= V0*COS(PSI0)*SIN(THETA0)*COS(PHI0) + V0*SIN(PSI0)*...
         SIN(PHI0) - W0*COS(PSI0)*SIN(THETA0)*SIN(PHI0) + ...
         W0*SIN(PSI0)*COS(PHI0)
A(7,11)= -U0*COS(PSI0)*SIN(THETA0) + V0*COS(PSI0)*COS(THETA0)*...
         SIN(PHI0) + W0*COS(PSI0)*COS(THETA0)*COS(PHI0)
A(7,12)= -U0*SIN(PSI0)*COS(THETA0) - V0*SIN(PSI0)*SIN(THETA0)*...
         SIN(PHI0) - V0*COS(PSI0)*COS(PHI0) - W0*SIN(PSI0)*...
         SIN(THETA0)*SIN(PHI0) + W0*COS(PSI0)*SIN(PHI0)
*
A(8,1) = SIN(PSI0)*COS(THETA0)
A(8,2) = SIN(PSI0)*SIN(THETA0)*SIN(PHI0) + COS(PSI0)*COS(PHI0)
A(8,3) = SIN(PSI0)*SIN(THETA0)*COS(PHI0) - COS(PSI0)*SIN(PHI0)
A(8,10)= V0*SIN(PSI0)*SIN(THETA0)*COS(PHI0) - V0*COS(PSI0)*...
         SIN(PHI0) - W0*SIN(PSI0)*SIN(THETA0)*SIN(PHI0) - ...
         W0*COS(PSI0)*COS(PHI0)
A(8,11)= -U0*SIN(PSI0)*SIN(THETA0) + V0*SIN(PSI0)*COS(THETA0)*...
         SIN(PHI0) + W0*SIN(PSI0)*COS(THETA0)*COS(PHI0)
A(8,12)= U0*COS(PSI0)*COS(THETA0) + V0*COS(PSI0)*SIN(THETA0)*...
         SIN(PHI0) - V0*SIN(PSI0)*COS(PHI0) + W0*COS(PSI0)*...
         SIN(THETA0)*COS(PHI0) + W0*SIN(PSI0)*SIN(PHI0)
*
A(9,1) = -SIN(THETA0)
A(9,2) = COS(THETA0)*SIN(PHI0)
A(9,3) = COS(THETA0)*COS(PHI0)
A(9,10)= V0*COS(THETA0)*COS(PHI0)-W0*COS(THETA0)*SIN(PHI0)
A(9,11)= -U0*COS(THETA0)-V0*SIN(THETA0)*SIN(PHI0) -...
          W0*SIN(THETA0)*COS(PHI0)
*
```

```
      A(10,4) = 1.0
      A(10,5) = SIN(PHI0)*TAN(THETA0)
      A(10,6) = COS(PHI0)*TAN(THETA0)
      A(10,10)= Q0*COS(PHI0)*TAN(THETA0) - R0*SIN(PHI0)*TAN(THETA0)
      A(10,11)= Q0*SIN(PHI0)/COS(THETA0)*1.0/COS(THETA0) + ...
                R0*COS(PHI0)/COS(THETA0)*1.0/COS(THETA0)
*
      A(11,5) = COS(PHI0)
      A(11,6) = -SIN(PHI0)
      A(11,10)= -Q0*SIN(PHI0) - R0*COS(PHI0)
*
      A(12,5) = SIN(PHI0)/COS(THETA0)
      A(12,6) = COS(PHI0)/COS(THETA0)
      A(12,10)= Q0*COS(PHI0)/COS(THETA0)-R0*SIN(PHI0)/COS(THETA0)
      A(12,11)= Q0*SIN(PHI0)/COS(THETA0)*TAN(THETA0) + ...
                R0*COS(PHI0)/COS(THETA0)*TAN(THETA0)
*
*     WRITE(10,200)((A(I,J),J=1,12),I=1,12)
*
*    CALCULATE THE B MATRIX
*
*


      B(1,1) = RHO/2*L**3*XRDR*U0*R0+RHO/2*L**2*(XRDR*U0*V0+U0**2*...
               2*XDRDR*DR)
      B(1,2) = U0*Q0*XQDB/2 + U0*W0*XWDB/2 + U0**2*XDBDB*DB
      B(1,3) = U0*Q0*XQDB/2 + U0*W0*XWDB/2 + U0**2*XDBDB*DB
      B(1,4) = U0*Q0*XQDS + U0*W0*XWDS +U0**2*2*XDSDS*DS+RHO/2*L**3*...
               XQDSN*U0*Q0*EPS + RHO/2*L**2*(XWDSN*U0*W0 + 2*XDSDSN*...
               U0**2*DS)*EPS
      B(1,5) = RHO/2*L**2*0.12*CD0*0.12*RPM
      B(1,6) = SIN(THETA0)
*
      B(2,1) = RHO/2*L**2*YDR*U0**2
      B(2,6) = -COS(THETA0)*SIN(PHI0)
*
      B(3,2) = U0**2*ZDB/2*RHO/2*L**2
      B(3,3) = U0**2*ZDB/2*RHO/2*L**2
      B(3,4) = U0**2*ZDS*RHO/2*L**2 + RHO/2*L**2*ZDSN*U0**2*EPS
      B(3,6) = -COS(THETA0)*COS(PHI0)
*
      B(4,2) =-RHO/2*L**3*U0**2*KDB/2
      B(4,3) = RHO/2*L**3*U0**2*KDB/2
      B(4,6) = -YB*COS(THETA0)*COS(PHI0) + ZB*COS(THETA0)*SIN(PHI0)
*
      B(5,2) = RHO/2*L**3*U0**2*MDB/2
      B(5,3) = RHO/2*L**3*U0**2*MDB/2
      B(5,4) = RHO/2*L**3*(U0**2*MDS+MDSN*U0**2*EPS)
      B(5,6) = XB*COS(THETA0)*COS(PHI0) + ZB*SIN(THETA0)
*
      B(6,1) = RHO/2*L**3*NDR*U0**2
      B(6,6) = -XB*COS(THETA0)*SIN(PHI0) - YB*SIN(THETA0)
*
*    FORMULATE THE A AND B MATRIX FOR STATE SPACE REPRESENTATION
*
*    MULTIPLY MMINV AND DF/DX
*
      DO 80 I = 1,6
         DO 70 J = 1,6
            SUM = 0.0
            DO 60 K = 1,6
            SUM = SUM + MMINV(I,K)*A(K,J)
60          CONTINUE
            AA(I,J) = SUM
70       CONTINUE
80    CONTINUE
*
```

```
*
*     MULTIPLY MMINV AND DF/DZ
*
*
      DO 50 I = 1,6
         DO 40 J = 7,12
         SUM = 0.0
             DO 30 K = 1,6
             SUM = SUM + MMINV(I,K)*A(K,J)
30           CONTINUE
             AA(I,J) = SUM
40       CONTINUE
50    CONTINUE
*
*
      DO 5 I = 7,12
         DO 6 J = 1,12
         AA(I,J) = A(I,J)
6        CONTINUE
5     CONTINUE
*
*
      WRITE(10,200)((AA(I,J),J=1,12),I=1,12)
200   FORMAT( 6E12.4)
*
*
*     MULTIPLY MMINV AND DF/DU
*
*
      DO 110 I = 1,6
         DO 100 J = 1,6
            SUM = 0.0
            DO 90 K = 1,6
            SUM = SUM + MMINV(I,K)*B(K,J)
90          CONTINUE
            BB(I,J) = SUM
100      CONTINUE
110   CONTINUE
*
*
      WRITE( 9,300)((BB(I,J),J=1,6),I=1,6)
300   FORMAT(6E12.4)
*
*
      DO 405 I = 1,6
      READ (2,401)(GKK(I,J), J=1,21)
405   WRITE(3,401)(GKK(I,J), J=1,21)
401   FORMAT(3E20.10)
*
*
      ELSE
      END IF
*
*     CALL ERRSET (209,256,-1,1,1)

*     PRINT*,INFO,ISTRAT,IOPT,IONED,IPRINT,IGRAD,NDV,NCON,DX,...
*     OBJ,GW,IDG,NGT,IC,DF,AW,NRA,NCOLA,WK,NRWK,...
*     IWK,NRIWK
      CALL DADS(INFO,ISTRAT,IOPT,IONED,IPRINT,IGRAD,NDV,NCON,DX,...
              VLB,VUB,OBJ,GW,IDG,NGT,IC,DF,AW,NRA,NCOLA,WK,NRWK,...
              IWK,NRIWK)
      IF (INFO.EQ. 0) DELPRT=0.2
*
DERIVATIVE
NOSORT
*
*
*
```

```
*****LINEAR MODEL*************************************************************
*
*
*    CALCULATE BB*U  PART OF XDOT = AA*X + BB*U
*
      DO 10 J = 1,6
         SUM = 0.0
         DO 15 K = 1,6
            SUM = SUM + BB(J,K)*UMOD(K)
15       CONTINUE
         XDOTU(J) = SUM
10    CONTINUE
*  CALCULATE AA*X
      DO 21 J= 1,12
         SUM = 0.0
         DO 25 K = 1,12
            SUM = SUM + AA(J,K)*X(K)
25       CONTINUE
         XDOTX(J) = SUM
21    CONTINUE
*  CALCULATE XDOT = AA*X + BB*U
      DO 31 J = 1,6
         XDOT(J) = XDOTX(J) + XDOTU(J)
31    CONTINUE
      DO 35 J = 7,12
         XDOT(J) = XDOTX(J)
35    CONTINUE
*
      UDOTM = XDOT(1)
      VDOTM = XDOT(2)
      WDOTM = XDOT(3)
      PDOTM = XDOT(4)

      QDOTM = XDOT(5)
      RDOTM = XDOT(6)
      XDOTM = XDOT(7)
      YDOTM = XDOT(8)
      ZDOTM = XDOT(9)
      PHMDOT= XDOT(10)
      THETMD= XDOT(11)
      PSMDOT= XDOT(12)
*     WRITE(8,600)
*   INTEGRATE XDOT TO GET THE STATE VECTOR X
*
      UM =INTGRL(6.0, UDOTM)
      VM= INTGRL(0.0, VDOTM)
      WM= INTGRL(0.0, WDOTM)
      PM= INTGRL(0.0, PDOTM)
      QM= INTGRL(0.0, QDOTM)
      RM= INTGRL(0.0, RDOTM)
      XPOSM = INTGRL(0.0, XDOTM)
      YPOSM = INTGRL(0.0, YDOTM)
      ZPOSM = INTGRL(0.0, ZDOTM)
      PHIM = INTGRL(0.0, PHMDOT)
      THETAM = INTGRL(0.0, THETMD)
      PSIM = INTGRL(0.0, PSMDOT)
*
```

```
 *
       X(1) = UM
       X(2) = VM
       X(3) = WM
       X(4) = PM
       X(5) = QM
       X(6) = RM
       X(7) = XPOSM
       X(8) = YPOSM
       X(9) = ZPOSM
       X(10) = PHIM
       X(11) = THETAM
       X(12) = PSIM
*
*      ZDEPTH = ZORD - X(9)
       THMANG = X(11)*57.3
       UMOD(1)=DRM
       UMOD(2)=DBM
*      DBPM= UMOD(3)
       UMOD(3)=DBM
       UMOD(4)=DSM
       UMOD(5)=DRPM
       UMOD(6)=DBOY
*
       PHANG=PHIM/0.0174532925
       THMANG=THETAM/0.0174532925
       PSMANG= PSIM/ 0.0174532925
       PITCHM=THMANG
       DEPTH=-ZPOSM


*
******CONTROL LAW**********************************************************
*
*
*      DBS = UMOD(2)
*      DBP = UMOD(3)
*      DS  = UMOD(4)
*      DR  = UMOD(1)
*
*
*      PUT IN STERN AND BOW PLANE STOPS
*
*      IF(ABS(DBS).GT.0.6) THEN
*        DBS = 0.6*ABS(DBS)/DBS
*      ENDIF
*      IF(ABS(DBP).GT.0.6) THEN
*        DBP = 0.6*ABS(DBP)/DBP
```

```
*      ENDIF
*      IF(ABS(DS).GT.0.6) THEN
*        DS = 0.6*ABS(DS)/DS
*      ENDIF
*
       INTGRD = (UM*UM+VM*VM+WM*WM+PM*PM+QM*QM+RM*RM+...
                XPOSM*XPOSM+(YPOSM-YORD)*(YPOSM-YORD)...
                +(ZPOSM-ORDDEP)*(ZPOSM-ORDDEP)+PHIM*PHIM+...
                THETAM*THETAM+PSIM*PSIM) + (DSM*DSM+DBM*DBM+DRM*DRM)
       OBJ1 = INTGRL(0.,(0.5)*INTGRD)
       OBJ = OBJ1


 DYNAMIC
       RN=TIME/(FINTIM/10.-DELT/10000.)
       PN=TIME/(FINTIM/20.-DELT/10000.)
       O=INT(RN)+1
       P=INT(PN)+1
       IF(O.GE.11) O=10
       IF(P.GE.20) P=20
*
* ADDITIONALLY THE PLANES SHOULD BE AT EQUILIBRIUM SO THE
* VEHICLE WILL PROCEED AT THIS NEW DEPTH WITHIN SOME TOLERANCE
*
       DSM=DX(O)
       DBM=DX(10+O)
       IF(O.GE.10) DSM=0.000
       IF(O.GE.10) DBM=0.000
       DRM=DX(20+P)
*      RPM=DX(30+O)
*
*          CONSTRAINTS FOR A DIVE
*
*  ORDERED DEPTH = ORDDEP
       GW(1) = (ZPOSM-ORDDEP)*.5
       GW(2) = (ORDDEP-ZPOSM)*.5
*  AUV'S FINAL STATE MUST BE LEVEL FLIGHT AS FOLLOWS
       GW(3) = THETAM
       GW(4) = -THETAM
       GW(5) = PHIM
       GW(6) = -PHIM
       GW(7) = PSIM
       GW(8) = -PSIM
       GW(9)=(YPOSM-YORD)/.4
       GW(10)=(YORD-YPOSM)/.4
       GW(11) = -ZPOSM
*
*   AVOIDING THE OBSTACLE
*
*      DIST1=SQRT((XPOSM-XOBS1)*(XPOSM-XOBS1)+...
*            (ZPOSM-ZOBS1)*(ZPOSM-ZOBS1))
*      IF (DIST1.LT.DSAVE1) DSAVE1=DIST1
*      GW(6) = (1.-DSAVE1)
       NDX=XPOSM/17.425
       NDZ=ZPOSM/17.425
       NDT=TIME*6./17.425
 TERMINAL
*      WRITE(11,66) XPOSM,YPOSM,DEPTH
*66    FORMAT (1X,F10.3,F10.3)
       IF(INFO.EQ.0) THEN
       PRINT*,O,P
 9000  CONTINUE
       ELSE
       ENDIF
       IF(INFO.EQ.0) CALL ENDJOB
       CALL RERUN
*
 END
 STOP
```

```
FILE: TNLO     DSL      A1

TITLE RUN:16-5  NONLINEAR AUV MODEL / STERN PLANE AND BOW PLANE SEPARATED
* (1) UPDATED:05/20/88
* (2) RIGHT OBJ EQUATION
* (3) ADS CONSTRAINTS ON DEPTH,PITCH,YAW,ROLL AND Y POSITION
* (4) CORRECTED OBSTACLE AVOIDANCE ROUTINE
********************ADSL SET-UP**********************************
FIXED ISTRAT, IOPT, IONED, IPRINT, INFO, IGRAD, NDV, NCON
FIXED IDG, NGT, IC, NRA, NCOLA, NRWK, IWK, NRIWK, O, H,D,C,PP
D      DIMENSION AW(42,42)
ARRAY WK(5000), IWK(1000)
ARRAY DX(40), VLB(40), VUB(40), GW(11), DF(41), IDG(11), IC(11)
PARAM NRA=42, NCOLA=42, NRWK=5000, NRIWK=1000
PARAM IGRAD=0, INFO=0, NDV=40, NCON=11, NGT=11
TABLE DX(1-2)=2*.0,DX(3-40)=38*0., IDG(1-10)=10*-1
TABLE IDG(11)=1*1
TABLE VLB(1-09)=09*-.17452, VLB(11-19)=09*-.2443,VLB(20)=0.,VLB(10)=0.
TABLE VUB(1-09)=09*.17452, VUB(11-19)=09*.2443,VUB(20)=0.,VUB(10)=0.
TABLE VLB(21-39)=19*-.62367,VUB(21-39)=19*.623627,VUB(40-41)=2*0.
TABLE VLB(40-41)=2*0.
PARAM ISTRAT=3, IOPT=1, IONED=1, IPRINT=0000
INCON  H=0, OBS1=0.,YZONE=0.
METHOD RECT
CONTROL FINTIM=21.0,DELT=.10
PRINT XPOS,YPOS,ZPOS,PITCH,THEANG,DR,DS
*RINT THETAD,W,DEPTH,PITCH,XPOS,DEPTH,NDX,NDZ,NDT
*RINT DS,DB,DR,DEPTH,PITCH,XPOS,YPOS,ZPOS,NDT
*AVE  THETA,W,Z,DEPTH,PITCH,DS,DB,BOWANG,STNANG
*RAPH(DE=TEK618) TIME,DS
*RAPH(DE=TEK618) TIME,DEPTH
*RAPH(DE=TEK618) TIME,WDOT
*RAPH(DE=TEK618) TIME,W
*RAPH(DE=TEK618) TIME,THETDD
*RAPH(DE=TEK618) TIME,THETAD
*RAPH(DE=TEK618) TIME,THETA
*RAPH(DE=TEK618) TIME,PITCH
*RAPH(DE=TEK618) TIME,BOWANG
*RAPH(DE=TEK618) TIME,STNANG
***************************DSL MODEL SET UP**************************
*
D       DIMENSION MM(6,6),G4(4),GK4(4),BR(4),HH(4)
D       DIMENSION  B(6,6),BB(6,6)
D       DIMENSION A(12,12), AA(12,12)
D       COMMON / BLOCK1 / F(12), FP(6), MMINV(6,6), UCF(4)
FIXED  N,IA,IDGT,IER,LAST,J,K,M,JJ,KK,I
INTEGER
ARRAY  WKAREA(54), X(12)
*
*
CONST
*
*     LONGITUDINAL HYDRODYNAMIC COEFFICIENTS
*
CONST XPP =            ,XQQ =            ,XRR =            ,XPR =            ,...
      XUDOT=           ,XWQ =            ,XVP =            ,XVR =            ,...
      XQDS=            ,XQDB=            ,XRDR=            ,XVV =            ,...
      XWW =            ,XVDR=            ,XWDS=            ,XWDB=            ,...
      XDSDS=           ,XDBDB=           ,XDRDR=           ,XQDSN=           ,...
      XWDSN=           ,XDSDSN=
*
```

```
*      LATERAL HYDRODYNAMIC COEFFICIENTS
*
CONST YPDOT=            ,YRDOT=             ,YPQ =              ,YQR =            ,...
      YVDOT=            ,YP   =             ,YR  =              ,YVQ =            ,...
      YWP  =            ,YWR  =             ,YV  =              ,YVW =            ,...
      YDR  =            ,CDY  =
*
*      NORMAL HYDRODYNAMIC COEFFICIENTS
*
CONST ZQDOT=            ,ZPP  =             ,ZPR  =             ,ZRR  =           ,...
      ZWDOT=            ,ZQ  =              ,ZVP  =             ,ZVR  =           ,...
      ZW  =             ,ZVV  =             ,ZDS  =             ,ZDB  =           ,...
      ZQN  =            ,ZWN  =             ,ZDSN=              ,CDZ  =

*
*      ROLL HYDRODYNAMIC COEFFITIENTS
*
CONST KPDOT=            , KRDOT=            ,KPQ  =             ,KQR  =           ,...
      KVDOT=            , KP  =             ,KR  =              ,KVQ=             ,...
      KWP  =            , KWR  =            ,KV  =              ,KVW  =           ,...
      KPN  =           , KDB  =
*
*      PITCH HYDRODYNAMIC COEFFICIENTS
*
CONST MQDOT=            , MPP  =            ,MPR  =             ,MRR  =           ,...
      MWDOT=            , MQ  =             ,MVP  =             ,MVR  =           ,...
      MW  =             , MVV  =            ,MDS  =             ,MDB  =           ,...
      MQN  =            , MWN  =            ,MDSN  =
*
*      YAW HYDRODYNAMIC COEFFICIENTS
*
CONST NPDOT=            , NRDOT=            ,NPQ  =             ,NQR  =           ,...
      NVDOT=            , NP  =             ,NR  =              ,NVQ  =           ,...
      NWP  =            , NWR  =            ,NV  =              ,NVW  =           ,...
      NDR  =
*
*      MASS CHARACTERISTICS OF THE FLOODED MARK IX VEHICLE
*
CONST WEIGHT =          , BOY  =            ,VOL  =             ,XG  =            ,...
      YG  =             , ZG  =             ,XB  =              ,ZB  =            ,...
      IX  =             , IY  =             ,IZ  =              ,IXZ  =           ,...
      IYZ  =            , IXY  =            ,YB  =                                ,...
      L  =              , RHO  =            ,G  =               ,NU  =            ,...
      A0  =             ,KPROP  =           ,NPROP  =    ,    X1TEST=             ,...
      DEGRUD= 0.0       ,DEGSTN=  0.0
*
*
*ONST XOBS1=36.0
*ONST ZOBS1=-12.0
*
*      INPUT INITIAL CONDITIONS HERE IF REQUIRED
*
```

```
INITIAL
*      DSAVE1=SQRT((XPOS-XOBS1)*(XPOS-XOBS1)+(ZPOS-ZOBS1)*(ZPOS-ZOBS1))
NOSORT
       ORDDEP = 17.425
*      YORD=40.0
       D=0
       H=H+1
       IF(H.EQ.1) THEN
       U = 0.0
       V = 0.0
       W = 0.0
       P = 0.0
       Q = 0.0
       R = 0.0
       XPOS = 0.0
       YPOS = 0.0
       ZPOS = 0.0
       PSI = 0.0
       THETA = 0.0
       PHI = 0.0
*
       U0 = 6.0
       V0 = 0.0
       W0 = 0.0
       P0 = 0.0
       Q0 = 0.0
       R0 = 0.0
       PHI0 = 0.0
       THETA0 = 0.0
       PSI0 = 0.0
       DB= 0.0
       DS = 0.0
       DR = 0.0
       RPM = 500

       LATYAW = 0.0
       NORPIT = 0.0
       RE = U0*L/NU
       CD0 =  .00385 + (1.296E-17)*(RE - 1.2E7)**2
*
*      DEFINE LENGTH FRACTIONS FOR GAUSS QUADUTURE TERMS
*
       G4(1) = 0.069431844
       G4(2) = 0.330009478
       G4(3) = 0.669990521
       G4(4) = 0.930568155
*
*      DEFINE WEIGHT FRACTIONS FOR GAUSS QUADUTURE TERMS
*
       GK4(1) = 0.1739274225687
       GK4(2) = 0.3260725774312
       GK4(3) = 0.3260725774312
       GK4(4) = 0.1739274225687
*
*      DEFINE THE BREADTH BB AND HEIGHT HH TERMS FOR THE INTEGRATION
*
       BR(1) = 75.7/12
       BR(2) = 75.7/12
       BR(3) = 75.7/12
       BR(4) = 55.08/12
*
```

```
      HH(1) = 16.38/12
      HH(2) = 31.85/12
      HH(3) = 31.85/12
      HH(4) = 23.76/12
*
      MASS = WEIGHT/G
*
      DIVAMP = DEGSTN*0.0174532925
      RUDAMP = DEGRUD*0.0174532925
*
*
      N = 6
      DO 15 J = 1,N
         DO 10 K = 1,N
         MMINV(J,K) = 0.0
         MM(J,K) = 0.0
10       CONTINUE
15    CONTINUE
*
*
*
*
*
*
      MM(1,1) = MASS -((RHO/2)*(L**3)*XUDOT)
      MM(1,5) = MASS*ZG
      MM(1,6) = -MASS*YG
*
      MM(2,2) = MASS -((RHO/2)*(L**3)*YVDOT)
      MM(2,4) = -MASS*ZG -((RHO/2)*(L**4)*YPDOT)
      MM(2,6) = MASS*XG - ((RHO/2)*(L**4)*YRDOT)
*
      MM(3,3) = MASS - ((RHO/2)*(L**3)*ZWDOT)
      MM(3,4) = MASS*YG
      MM(3,5) = -MASS*XG -((RHO/2)*(L**4)*ZQDOT)
*
      MM(4,2) = -MASS*ZG - ((RHO/2)*(L**4)*KVDOT)
      MM(4,3) = MASS*YG
      MM(4,4) = IX - ((RHO/2)*(L**5)*KPDOT)
      MM(4,5) = -IXY
      MM(4,6) = -IXZ -((RHO/2)*(L**5)*KRDOT)

      MM(5,1) = MASS*ZG
      MM(5,3) = -MASS*XG -((RHO/2)*(L**4)*MWDOT)
      MM(5,4) = -IXY
      MM(5,5) = IY -((RHO/2)*(L**5)*MQDOT)

      MM(5,6) = -IYZ
*
      MM(6,1) = -MASS*YG
      MM(6,2) = MASS*XG -((RHO/2)*(L**4)*NVDOT)
      MM(6,4) = -IXZ - ((RHO/2)*(L**5)*NPDOT)
      MM(6,5) = -IYZ
      MM(6,6) = IZ - ((RHO/2)*(L**5)*NRDOT)
*
```

```
*
      LAST = N*N+3*N
      DO 20 M = 1,LAST
      WKAREA(M) = 0.0
20    CONTINUE
*
      IER = 0
      IA = 6
      IDGT = 4
      WRITE( 8,400)((MM(I,J), J = 1,6),I = 1,6)
*
      CALL LINV2F(MM,N,IA,MMINV,IDGT,WKAREA,IER)
*
      WRITE( 8,400)((MMINV(I,J), J = 1,6),I = 1,6)
400   FORMAT(6E12.4)
*
      ELSE
      ENDIF
*
*
      CALL DADS(INFO,ISTRAT,IOPT,IONED,IPRINT,IGRAD,NDV,NCON,DX,...
              VLB,VUB,OBJ,GW,IDG,NGT,IC,DF,AW,NRA,NCOLA,WK,NRWK,...
              IWK,NRIWK)
C     IF(H.EQ.1) THEN
C        WK(12) = .002
C     CALL DADS(INFO,ISTRAT,IOPT,IONED,IPRINT,IGRAD,NDV,NCON,DX,...
C             VLB,VUB,OBJ,GW,IDG,NGT,IC,DF,AW,NRA,NCOLA,WK,NRWK,...
C             IWK,NRIWK)
      IF(INFO.EQ.0) DELPRT = 0.2
*     IF(INFO.EQ.0) DELPLT = 0.2
*
*
*
DERIVATIVE
NOSORT
*
*
*     PROPULSION MODEL
*
*
      SIGNU = 1.0
      IF (U.LT.0.0) SIGNU = -1.0
      IF (ABS(U).LT.X1TEST) U = X1TEST
      SIGNN = 1.0
      IF (RPM.LT.0.0) SIGNN = -1.0
      ETA = 0.012*RPM/U
      RE = U*L/NU
      CD0 =  .00385 + (1.296E-17)*(RE - 1.2E7)**2
      CT  = 0.008*L**2*ETA*ABS(ETA)/(A0)
      CT1 = 0.008*L**2/(A0)
      EPS = -1.0+SIGNN/SIGNU*(SQRT(CT+1.0)-1.0)/(SQRT(CT1+1.0)-1.0)
      XPROP = CD0*(ETA*ABS(ETA) - 1.0)
*
*
*
*     CALCULATE THE DRAG FORCE, INTEGRATE THE DRAG OVER THE VEHICLE
*     INTEGRATE USING A 4 TERM GAUSS QUADUTURE
*
*
      LATYAW = 0.0
      NORPIT = 0.0
      DO 500 K = 1,4
         UCF(K) = SQRT((V+G4(K)*R*L)**2 + (W-G4(K)*Q*L)**2)
         IF(UCF(K).GT.1E-10) THEN
```

```
         TERM0  = (RHO/2)*(CDY*HH(K)*(V+G4(K)*R*L)**2 +...
                  CDZ*BR(K)*(W-G4(K)*Q*L)**2)
         TERM1  = TERM0*(V+G4(K)*R*L)/UCF(K)
         TERM2  = TERM0*(W-G4(K)*Q*L)/UCF(K)
         LATYAW = LATYAW + TERM1*GK4(K)*L
         NORPIT = NORPIT + TERM2*GK4(K)*L
         END IF
500   CONTINUE
*
*
*     FORCE EQUATIONS
*
*
*    LONGITUDINAL FORCE
*
      FP(1) = MASS*V*R - MASS*W*Q + MASS*XG*Q**2 + MASS*XG*R**2-...
             MASS*YG*P*Q - MASS*ZG*P*R + (RHO/2)*L**4*(XPP*P**2 +...
             XQQ*Q**2 + XRR*R**2 + XPR*P*R) +(RHO/2)*L**3*(XWQ*W*Q +...
             XVP*V*P+XVR*V*R+U*Q*(XQDS*DS+XQDB*DB)+XRDR*U*R*DR)+...
             (RHO/2)*L**2*(XVV*V**2 + XWW*W**2 + XVDR*U*V*DR + U*W*...
             (XWDS*DS+XWDB*DB)+U**2*(XDSDS*DS**2+XDBDB*DB**2+...
             XDRDR*DR**2))-(WEIGHT -BOY)*SIN(THETA) +(RHO/2)*L**3* ...
             XQDSN*U*Q*DS*EPS+(RHO/2)*L**2*(XWDSN*U*W*DS+XDSDSN*U**2*...
             DS**2)*EPS +(RHO/2)*L**2*U**2*XPROP
*
*    LATERAL FORCE
*
      FP(2) = -MASS*U*R - MASS*XG*P*Q + MASS*YG*R**2 - MASS*ZG*Q*R +...
             (RHO/2)*L**4*(YPQ*P*Q + YQR*Q*R)+(RHO/2)*L**3*(YP*U*P +...
             YR*U*R + YVQ*V*Q + YWP*W*P + YWR*W*R) + (RHO/2)*L**2*  ...
             (YV*U*V + YVW*V*W +YDR*U**2*DR) -LATYAW +(WEIGHT-BOY)*...
             COS(THETA)*SIN(PHI)
*
*    NORMAL FORCE
*
      FP(3) = MASS*U*Q - MASS*V*P - MASS*XG*P*R - MASS*YG*Q*R +     ...
             MASS*ZG*P**2 + MASS*ZG*Q**2 + (RHO/2)*L**4*(ZPP*P**2 +...
             ZPR*P*R + ZRR*R**2) + (RHO/2)*L**3*(ZQ*U*Q + ZVP*V*P +...
             ZVR*V*R) +(RHO/2)*L**2*(ZW*U*W + ZVV*V**2 + U**2*(ZDS*...
             DS+ZDB*DB))-NORPIT+(WEIGHT-BOY)*COS(THETA)*COS(PHI)+...
             (RHO/2)*L**3*ZQN*U*Q*EPS +(RHO/2)*L**2*(ZWN*U*W +ZDSN*...
             U**2*DS)*EPS
*
*    ROLL FORCE
*
      FP(4) = -IZ*Q*R +IY*Q*R -IXY*P*R +IYZ*Q**2 -IYZ*R**2 +IXZ*P*Q +...
             MASS*YG*U*Q -MASS*YG*V*P -MASS*ZG*W*P+(RHO/2)*L**5*(KPQ*...
             P*Q + KQR*Q*R) +(RHO/2)*L**4*(KP*U*P +KR*U*R + KVQ*V*Q +...
             KWP*W*P + KWR*W*R) +(RHO/2)*L**3*(KV*U*V + KVW*V*W) +  ...
             (YG*WEIGHT - YB*BOY)*COS(THETA)*COS(PHI) - (ZG*WEIGHT - ...
             ZB*BOY)*COS(THETA)*SIN(PHI) + (RHO/2)*L**4*KPN*U*P*EPS+ ...
             (RHO/2)*L**3*U**2*KPROP +MASS*ZG*U*R
*
```

```
*     PITCH FORCE
*
      FP(5) = -IX*P*R +IZ*P*R +IXY*Q*R -IYZ*P*Q -IXZ*P**2 +IXZ*R**2 -...
              MASS*XG*U*Q + MASS*XG*V*P + MASS*ZG*V*R - MASS*ZG*W*Q +...
              (RHO/2)*L**5*(MPP*P**2 +MPR*P*R +MRR*R**2)+(RHO/2)*L**4*...
              (MQ*U*Q + MVP*V*P + MVR*V*R) + (RHO/2)*L**3*(MW*U*W + ...
              MVV*V**2+U**2*(MDS*DS+MDB*DB))+ NORPIT -(XG*WEIGHT- ...
              XB*BOY)*COS(THETA)*COS(PHI)
              (RHO/2)*L**4*MQN*U*Q*EPS                            +...
              (RHO/2)*L**3*(MWN*U*W+MDSN*U**2*DS)*EPS-            +...
              (ZG*WEIGHT-ZB*BOY)*SIN(THETA)                        ...
*
*     YAW FORCE
*
      FP(6) = -IY*P*Q +IX*P*Q +IXY*P**2 -IXY*Q**2 +IYZ*P*R -IXZ*Q*R -...
              MASS*XG*U*R + MASS*XG*W*P - MASS*YG*V*R + MASS*YG*W*Q +...
              (RHO/2)*L**5*(NPQ*P*Q + NQR*Q*R) +(RHO/2)*L**4*(NP*U*P+...
              NR*U*R + NVQ*V*Q +NWP*W*P + NWR*W*R) +(RHO/2)*L**3*(NV*...
              U*V + NVW*V*W + NDR*U**2*DR) - LATYAW + (XG*WEIGHT - ...
              XB*BOY)*COS(THETA)*SIN(PHI)+(YG*WEIGHT)*SIN(THETA)...
              +(RHO/2)*L**3*U**2*NPROP-YB*BOY*SIN(THETA)
*
*     IF(Z.EQ.50.0)THEN
*        WRITE (8,500)(FP(I), I = 1,6)
*        Z = 0.0
*     END IF
*
*
*     NOW COMPUTE THE F(1-6) FUNCTIONS
*
      DO 600 J = 1,6
             F(J) = 0.0
      DO 600 K = 1,6
             F(J) = MMINV(J,K)*FP(K) + F(J)
600   CONTINUE
*
*     THE LAST SIX EQUATIONS COME FROM THE KINEMATIC RELATIONS
*
*     FIRST SET THE DRIFT CURRENT VALUES
*
      UCO = 0.0
      VCO = 0.0
      WCO = 0.0
*
*     INERTIAL POSITION RATES F(7-9)
*
      F(7) = UCO + U*COS(PSI)*COS(THETA) + V*(COS(PSI)*SIN(THETA)*...
             SIN(PHI) - SIN(PSI)*COS(PHI)) + W*(COS(PSI)*SIN(THETA)*...
             COS(PHI) + SIN(PSI)*SIN(PHI))
*
      F(8) = VCO + U*SIN(PSI)*COS(THETA) + V*(SIN(PSI)*SIN(THETA)*...
             SIN(PHI) + COS(PSI)*COS(PHI)) + W*(SIN(PSI)*SIN(THETA)*...
             COS(PHI) - COS(PSI)*SIN(PHI))
*
      F(9) = WCO - U*SIN(THETA) +V*COS(THETA)*SIN(PHI) +W*COS(THETA)*...
             COS(PHI)
*
*     EULER ANGLE RATES F(10-12)
*
      F(10) = P + Q*SIN(PHI)*TAN(THETA) + R*COS(PHI)*TAN(THETA)
*
      F(11) = Q*COS(PHI) - R*SIN(PHI)
*
      F(12) = Q*SIN(PHI)/COS(THETA) + R*COS(PHI)/COS(THETA)
```

```
*
*
*      IF (Z.EQ.1.0)WRITE (9,500)(F(I), I = 1,12)
*00    FORMAT(6E12.4)
*      Z = Z + 1
*
*
       UDOT = F(1)
       VDOT = F(2)
       WDOT = F(3)
       PDOT = F(4)
       QDOT = F(5)
       RDOT = F(6)
       XDOT = F(7)
       YDOT = F(8)
       ZDOT = F(9)
       PHIDOT = F(10)
       THETAD = F(11)
       PSIDOT = F(12)
*
       U = INTGRL (U0,UDOT)
*      X(1) = U
       V = INTGRL(0.0,VDOT)
*      X(2) = V
       W = INTGRL(0.0,WDOT)
*      X(3) = W
       P = INTGRL(0.0,PDOT)
*      X(4) = P
       Q = INTGRL(0.0,QDOT)
*      X(5) = Q
       R = INTGRL(0.0,RDOT)
*      X(6) = R
       XPOS = INTGRL(0.0,XDOT)
*      X(7) = XPOS
       YPOS = INTGRL(0.0,YDOT)
*      X(8) = YPOS
       Z = INTGRL(0.0,ZDOT)
*      X(9) = ZPOS
       PHI = INTGRL(0.0,PHIDOT)
*      X(10) = PHI
       THETA = INTGRL(0.0,THETAD)
*      X(11) = THETA
       PSI = INTGRL(0.0,PSIDOT)
*      X(12) = PSI
*
       PHIANG = PHI/0.0174532925
       THEANG = THETA/0.0174532925
       PSIANG = PSI/0.0174532925
       ZPOS=-Z
*
       DEPTH=ZPOS
       PITCH=THEANG
       BOWANG=(DB/.01745)
       STNANG=(DS/.01745)
       INTGRD = (U*U+V*V+W*W+P*P+Q*Q+R*R+XPOS*XPOS+(YPOS-YORD)*...
               (YPOS-YORD)+(Z-ORDDEP)*(Z-ORDDEP)+PHI*PHI+...
                THETA*THETA+PSI*PSI) + (DS*DS+DB*DB)+(DR*DR)
       OBJ1 = INTGRL(0.,(0.5)*INTGRD)
       OBJ = OBJ1
```

```
*
DYNAMIC
      RN=TIME/(FINTIM/10.-DELT/10000.)
      PN=TIME/(FINTIM/20.-DELT/10000.)
      O=INT(RN)+1
      PP=INT(PN)+1
      IF(O.GE.10) O=10
      IF(PP.GE.20) PP=20
*
* ADDITIONALLY THE PLANES SHOULD BE AT EQUILIBRIUM SO THE
* VEHICLE WILL PROCEED AT THIS NEW DEPTH WITHIN SOME TOLERANCE
*
      DS=DX(O)
      DB=DX(10+O)
      IF(O.GE.10) DS=0.
      IF(O.GE.10) DB=0.
      DR=DX(20+PP)
*     RPM=DX(30+O)
*
*         CONSTRAINTS FOR A DIVE
*
*  ORDERED DEPTH = ORDDEP
      GW(1) = (Z-ORDDEP)*.5
      GW(2) = (ORDDEP-Z)*.5
*  AUV'S FINAL STATE MUST BE LEVEL FLIGHT AS FOLLOWS
      GW(3) = THETA
      GW(4) = -THETA
      GW(5)= (YPOS-YORD)/.4
      GW(6)= (YORD-YPOS)/.4
      GW(7)=PSI
      GW(8)=-PSI
      GW(9)=PHI
      GW(10)=-PHI
      GW(11)=ZPOS
*
*   AVOIDING THE OBSTACLE
*
*     DIST1=SQRT((XPOS-XOBS1)*(XPOS-XOBS1)+(ZPOS-ZOBS1)*(ZPOS-ZOBS1))
*     IF (DIST1.LT.DSAVE1) DSAVE1=DIST1
*     GW(6) = (1.-DSAVE1)
      NDX=XPOS/17.425
      NDZ=ZPOS/17.425
      NDT=TIME*6./17.425
TERMINAL
      IF(INFO.EQ.0) THEN
*     PRINT*,DSAVE1
*9999 FORMAT(1X,E15.4)
 9000 CONTINUE
      ELSE
      ENDIF
      IF(INFO.EQ.0) CALL ENDJOB
      CALL RERUN
*
END
STOP
```

```
FILE: TX        DSL       A1

TITLE LINEAR AUV MODEL / STERN PLANE AND BOW PLANE SEPARATED
TITLE WITH COMMANDS TO NONLINEAR MODEL
* (1) UPDATED:05/30/88
* (3) RIGHT OBJ EQUATION
* (4) ADS CONSTRAINTS ON DEPTH AND PITCH
* (5) OBSTACLE FURTHER DOWN THE TRAJECTORY AND ABOVE IT
* (6) CORRECT OBSTACLE AVOIDANCE ROUTINE ADDED
********************ADSL SET-UP*********************************
FIXED ISTRAT, IOPT, IONED, IPRINT, INFO, IGRAD, NDV, NCON
FIXED IDG, NGT, IC, NRA, NCOLA, NRWK, IWK, NRIWK, O, H,D,C,PP
D      DIMENSION AW(42,42)
ARRAY WK(4000), IWK(1000)
ARRAY DX(40), VLB(40), VUB(40), GW(07), DF(41), IDG(07), IC(07)
PARAM NRA=42, NCOLA=42, NRWK=4000, NRIWK=1000
PARAM IGRAD=0, INFO=0, NDV=40, NCON=07, NGT=07
TABLE DX(1-2)=2*.0,DX(3-21)=19*0., IDG(1-6)=6*-1
TABLE DX(22-40)=19*0.
TABLE IDG(7-0)=1*1
TABLE VLB(1-9)=9*-.17452, VLB(11-19)=9*-.2443,VLB(10)=0.,VLB(20)=0.
TABLE VUB(1-9)=9*.17452, VUB(11-19)=9*.2443,VUB(10)=0.,VUB(20)=0.
TABLE VLB(21-39)=19*-.523627,VUB(21-39)=19*.523627,VUB(40-41)=2*0.
TABLE VLB(40-41)=2*0.
PARAM ISTRAT=3, IOPT=1, IONED=1, IPRINT=0000
INCON  H=0, OBS1=0.,YZONE=0.
METHOD RECT
CONTROL FINTIM=21., DELT=.1
PRINT XPOS,YPOS,ZPOS,XPOSM,YPOSM,ZPOSM
*RINT DS,DSM,DBPM,DBP,PITCHM,PITCH,XPOSM,YPOSM,XPOS,YPOS,ZPOSM,ZPOS,NDT
*RINT YPOSM,YPOS
*RINT THETAD,W,DEPTH,PITCH,XPOS,DEPTH,NDX,NDZ,NDT
*AVE  THETA,W,Z,DEPTH,PITCH,DS,DB,BOWANG,STNANG
*RAPH(DE=TEK618) TIME,DS
*RAPH(DE=TEK618) TIME,DEPTH
*RAPH(DE=TEK618) TIME,WDOT
*RAPH(DE=TEK618) TIME,W
*RAPH(DE=TEK618) TIME,THETDD
*RAPH(DE=TEK618) TIME,THETAD
*RAPH(DE=TEK618) TIME,THETA
*RAPH(DE=TEK618) TIME,PITCH
*RAPH(DE=TEK618) TIME,BOWANG
*RAPH(DE=TEK618) TIME,STNANG
******************D S L MODEL FOR LINEAR SIMULATION ******************
*****************AND NON-LINEAR SIMULATION VARYING CONTROL LAW*********
*                         LINEAR MODEL/NON-LINEAR MODEL
D       COMMON/BLOCK1/ MMINV(6,6), MM(6,6), AA(12,12), BB(6,6)
D       COMMON/BLOCK2/ B(6,6),A(12,12), UMOD(6),GKK(6,21)
D       COMMON/BLOCK3/ F(12), FP(6), UCF(4)
D       COMMON/BLOCK4/ G4(4),GK4(4),BR(4),HH(4)
D       COMMON/BLOCK5/ XDOT(12),XDOTX(12), XDOTU(6)
FIXED  N,IA,IDGT,IER,LAST,J,K,M,JJ,KK,I
INTEGER
ARRAY  WKAREA(54), X(12)
*
*
*
```

```
CONST
*
*      LONGITUDINAL HYDRODYNAMIC COEFFICIENTS
*
CONST XPP =           ,XQQ =           ,XRR =           ,XPR =           ,...
      XUDOT=          ,XWQ =           ,XVP =           ,XVR =           ,...
      XQDS=           ,XQDB=           ,XRDR=           ,XVV =           ,...
      XWW =           ,XVDR=           ,XWDS=           ,XWDB=           ,...
      XDSDS=          ,XDBDB=          ,XDRDR=          ,XQDSN=          ,...
      XWDSN=          ,XDSDSN=
*
*      LATERAL HYDRODYNAMIC COEFFICIENTS
*
CONST YPDOT=          ,YRDOT=          ,YPQ =           ,YQR =           ,...
      YVDOT=          ,YP   =          ,YR =            ,YVQ =           ,...
      YWP =           ,YWR =           ,YV =            ,YVW =           ,...
      YDR =           ,CDY =
*
*      NORMAL HYDRODYNAMIC COEFFICIENTS
*
CONST ZQDOT=          ,ZPP =           ,ZPR =           ,ZRR =           ,...
      ZWDOT=          ,ZQ =            ,ZVP =           ,ZVR =           ,...
      ZW =            ,ZVV =           ,ZDS =           ,ZDB =           ,...
      ZQN =           ,ZWN =           ,ZDSN=           ,CDZ =
*
*      ROLL HYDRODYNAMIC COEFFITIENTS
*
CONST KPDOT=          , KRDOT=         ,KPQ =           ,KQR =           ,...
      KVDOT=          , KP =           ,KR =            ,KVQ=            ,...
      KWP =           , KWR =          ,KV =            ,KVW =           ,...
      KPN =          , KDB =
*
*      PITCH HYDRODYNAMIC COEFFICIENTS
*
CONST MQDOT=          , MPP =          ,MPR =           ,MRR =           ,...
      MWDOT=          , MQ =           ,MVP =           ,MVR =           ,...
      MW =            , MVV =          ,MDS =           ,MDB =           ,...
      MQN =           , MWN =          ,MDSN =
*
*      YAW HYDRODYNAMIC COEFFICIENTS
*
CONST NPDOT=          , NRDOT=         ,NPQ =           ,NQR =           ,...
      NVDOT=          , NP =           ,NR =            ,NVQ =           ,...
      NWP =           , NWR =          ,NV =            ,NVW =           ,...
      NDR =
*
*      MASS CHARACTERISTICS OF THE FLOODED MARK IX VEHICLE
*
CONST WEIGHT =        , BOY =          ,VOL =           ,XG =            ,...
      YG =            , ZG =           ,XB =            ,ZB =            ,...
      IX =            , IY =           ,IZ =            ,IXZ =           ,...
      IYZ =           , IXY =          ,YB =                             ,...
      L =             , RHO =          ,G =             ,NU =            ,...
      A0 =            ,KPROP =         ,NPROP =     ,    X1TEST=         ,...
      DEGRUD= 0.0     ,DEGSTN=  0.0
*
*
CONST  XOBS1=36.0
CONST  ZOBS1= -12.0
```

```
*      INPUT INITIAL CONDITIONS HERE IF REQUIRED
*
INITIAL
*
*      DSAVE1=SQRT((XPOSM-XOBS1)*(XPOSM-XOBS1)+...
*           (ZPOSM-ZOBS1)*(ZPOSM-ZOBS1))
*      DSAVEV=DSAVE1
*      INITIALIZE ALL MATRICES AND ARRAYS TO ZERO
NOSORT
       ORDDEP=20.0
       YORD=40.0
       D=0
       H=H+1
       IF (H.EQ.1) THEN
       N = 6
       DO 2  J = 1,N
          JJ= J+N
          DO  1 K = 1,N
          KK= K+N
          KKK= KK + N
          MMINV(J,K) = 0.0
          X(J) = 0.0
          X(JJ) = 0.0
          XDOT(J) = 0.0
          XDOT(JJ) = 0.0
          XDOTX(J) = 0.0
          XDOTX(JJ) = 0.0
          XDOTU(J) = 0.0
*         UMOD(J) = 0.0
          MM(J,K) = 0.0
          BB(J,K) = 0.0
          B(J,K) = 0.0
          AA(J,K)= 0.0
          AA(JJ,KK)= 0.0
          AA(J,KK)= 0.0
          AA(JJ,K)= 0.0
          A(J,KK)= 0.0
          A(JJ,K) = 0.0
          A(J,K) = 0.0
          A(JJ,KK)= 0.0
          GKK(J,K)= 0.0
          GKK(J,KK)=0.0
          GKK(J,KKK)=0.0
1         CONTINUE
2      CONTINUE
*
*      INPUT THE LINEARIZATION POINT PARAMETERS
*
       U0 =6.0
       V0 = 0.0
       W0 = 0.0
       P0 = 0.0
       Q0 = 0.0
       R0 = 0.0
       PHI0 = 0.0
       THETA0 = 0.0
       PSI0 = 0.0
       SUM = 0.0
       JFLAG = 0
       IFLAG = 0
       KFLAG = 0
*
```

```
*     INPUT THE MODEL STATES INITIAL CONDITIONS
*
      UM = 6.0
      VM = 0.0
      WM = 0.0
      PM = 0.0
      QM = 0.0
      RM = 0.0
      XPOSM = 0.0
      YPOSM = 0.0
      ZPOSM = 0.0
      PHIM = 0.0
      THETAM = 0.0
      PSIM = 0.0
      U  = 6.0
      V  = 0.0
      W  = 0.0
      P  = 0.0
      Q  = 0.0
      R  = 0.0
      XPOS  = 0.0
      YPOS  = 0.0
      ZPOS  = 0.0
      PHI  = 0.0
      THETA  = 0.0
      PSI  = 0.0
*
*
*     INPUT THE VEHICLE INITIAL CONDITIONS
*
*
*     INITIALIZE THE CONTROLS
*
      DELBOY= 0.0
      DBOY=0.
      DS= 0.0
*     DSM=0.0
*     DBM=0.0
      DB=0.0
      DR= 0.0
      DRM=0.0
      DRPM=0.0
      RPM = 500.0
      LATYAW = 0.0
      NORPIT = 0.0
*
*
      MASS = WEIGHT/G
*
      DIVAMP = DEGSTN*0.0174532925
      RUDAMP = DEGRUD*0.0174532925
*
*     DEFINE LENGTH FRACTIONS FOR GAUSS QUADUTURE TERMS
*
      G4(1) = 0.069431844
      G4(2) = 0.330009478
      G4(3) = 0.669990521
      G4(4) = 0.930568155
*
*     DEFINE WEIGHT FRACTIONS FOR GAUSS QUADUTURE TERMS
*
      GK4(1) = 0.1739274225687
      GK4(2) = 0.3260725774312
      GK4(3) = 0.3260725774312
      GK4(4) = 0.1739274225687
*
```

```
*      DEFINE THE BREADTH BB AND HEIGHT HH TERMS FOR THE INTEGRATION
*
       BR(1) = 75.7/12
       BR(2) = 75.7/12
       BR(3) = 75.7/12
       BR(4) = 55.08/12
*
       HH(1) = 16.38/12
       HH(2) = 31.85/12
       HH(3) = 31.85/12
       HH(4) = 23.76/12
*
*      THE LINEAR PROPULSION MODEL
*
*
*      ETA = 0.012*RPM/U0
       ETA = 1.0
       RE = U0*L/NU
       CD0 =   .00385 + (1.296E-17)*(RE - 1.2E7)**2
       CT  = 0.008*L**2*ETA*ABS(ETA)/(A0)
       CT1 = 0.008*L**2/(A0)
       EPS = -1.0+(SQRT(CT+1.0)-1.0)/(SQRT(CT1+1.0)-1.0)
       XPROP = CD0*(ETA*ABS(ETA) - 1.0)

*
*      CALCULATE THE MASS MATRIX
*
       MM(1,1) = MASS -((RHO/2)*(L**3)*XUDOT)
       MM(1,5) = MASS*ZG
       MM(1,6) = -MASS*YG

       MM(2,2) = MASS -((RHO/2)*(L**3)*YVDOT)
       MM(2,4) = -MASS*ZG -((RHO/2)*(L**4)*YPDOT)
       MM(2,6) = MASS*XG - ((RHO/2)*(L**4)*YRDOT)

       MM(3,3) = MASS - ((RHO/2)*(L**3)*ZWDOT)
       MM(3,4) = MASS*YG
       MM(3,5) = -MASS*XG -((RHO/2)*(L**4)*ZQDOT)

       MM(4,2) = -MASS*ZG - ((RHO/2)*(L**4)*KVDOT)
       MM(4,3) = MASS*YG
       MM(4,4) = IX - ((RHO/2)*(L**5)*KPDOT)
       MM(4,5) = -IXY
       MM(4,6) = -IXZ -((RHO/2)*(L**5)*KRDOT)

       MM(5,1) = MASS*ZG
       MM(5,3) = -MASS*XG -((RHO/2)*(L**4)*MWDOT)
       MM(5,4) = -IXY
       MM(5,5) = IY -((RHO/2)*(L**5)*MQDOT)
       MM(5,6) = -IYZ

       MM(6,1) = -MASS*YG
       MM(6,2) = MASS*XG -((RHO/2)*(L**4)*NVDOT)
       MM(6,4) = -IXZ - ((RHO/2)*(L**5)*NPDOT)
       MM(6,5) = -IYZ
       MM(6,6) = IZ - ((RHO/2)*(L**5)*NRDOT)
*
*
       LAST = N*N+3*N
       DO 20 M = 1,LAST
       WKAREA(M) = 0.0
20     CONTINUE
*
       IER = 0
       IA = 6
       IDGT = 4
*
```

```
      CALL LINV2F(MM,N,IA,MMINV,IDGT,WKAREA,IER)
*
*     CALCULATE THE A MATRIX FOR THE LINEAR MODEL
*
*
*
      A(1,1) = RHO/2*L**3*(XQDS*DS*Q0+XQDB/2*DBP*Q0+XRDR*R0*DR)+
     .         RHO/2*L**2*(XVDR*V0*DR+XWDS*DS*W0+XWDB/2*DBP*W0 +
     .         2*U0*(XDSDS*DS**2 + XDBDB/2*DBP**2 + XDRDR*DR**2))+
     .         RHO/2*L**3*XQDSN*Q0*DS*EPS+RHO/2*L**2*(XWDSN*W0*DS+
     .         2*XDSDSN*U0*DS**2)*EPS+RHO*L**2*U0*XPROP+RHO/2*L**3*
     .         XQDB/2*DBS*Q0+RHO/2*L**2*XWDB/2*DBS*W0+RHO*L**2*U0*
     .         XDBDB/2*DBS**2
      A(1,2) = MASS*R0+RHO/2*L**3*(XVP*P0+ XVR*R0) + RHO/2*L**2*
     .         (2*XVV*V0 + XVDR*U0*DR)
      A(1,3) = -MASS*Q0 + RHO/2*L**3*(XWQ*Q0)+RHO/2*L**2*(2*XWW*W0+
     .         XWDS*DS*U0+(XWDB/2*DBP+XWDB/2*DBS)*U0 +XWDSN*U0*DS*EPS)
      A(1,4) = -MASS*YG*Q0-MASS*ZG*R0+ RHO/2*L**4*(2*XPP*P0+XPR*R0)
     .         + RHO/2*L**3*(XVP*V0)
      A(1,5) = -MASS*W0+2*MASS*XG*Q0 -MASS*YG*P0+RHO/2*L**4*2*XQQ*Q0
     .         +RHO/2*L**3*(XWQ*W0+XQDS*DS*U0+XQDB/2*DBP*U0)+RHO/2*
     .         L**3*XQDSN*U0*DS*EPS+RHO/2*L**3*XQDB/2*DBS*U0
      A(1,6) = MASS*V0+2*MASS*XG*R0-MASS*ZG*P0+RHO/2*L**4*(2*XRR*R0
     .         + XPR*P0) + RHO/2*L**3*(XVR*V0 + XRDR*U0*DR)
      A(1,11)= -(WEIGHT - BOY)*COS(THETA0)
*
      A(2,1) = -MASS*R0+RHO/2*L**3*(YP*P0+YR*R0)+RHO/2*L**2*(YV*V0+
     .         2*YDR*U0*DR)
      A(2,2) = RHO/2*L**3*YVQ*Q0+RHO/2*L**2*(YV*U0+YVW*W0)
      A(2,3) = MASS*P0+ RHO/2*L**3*(YWP*P0+YWR*R0)+RHO/2*L**2*YVW*V0
      A(2,4) = MASS*W0-MASS*XG*Q0+2*MASS*YG*P0+RHO/2*L**4*YPQ*Q0+
     .         RHO/2*L**3*(YP*U0+ YWP*W0)
      A(2,5) = -MASS*XG*P0-MASS*ZG*R0+RHO/2*L**4*(YPQ*P0+YQR*R0) +
     .         RHO/2*L**3*YVQ*V0
      A(2,6) = -MASS*U0+2*MASS*YG*R0-MASS*ZG*Q0+RHO/2*L**4*YQR*Q0 +
     .         RHO/2*L**3*(YR*U0 + YWR*W0)
      A(2,10)= (WEIGHT - BOY)*COS(THETA0)*COS(PHI0)
      A(2,11)= -(WEIGHT - BOY)*SIN(THETA0)*SIN(PHI0)
*
      A(3,1) = MASS*Q0+RHO/2*L**3*ZQ*Q0+RHO/2*L**2*(ZW*W0+2*U0*ZDS*DS
     .         +2*U0*ZDB/2*DBP+(ZWN*W0+2*ZDSN*U0*DS)*EPS)+RHO/2*L**3*
     .         ZQN*Q0*EPS+ RHO/2*L**2*2*U0*ZDB/2*DBS
      A(3,2) = -MASS*P0+RHO/2*L**3*(ZVP*P0+ZVR*R0)+RHO/2*L**2*2*ZVV*V0
      A(3,3) = RHO/2*L**2*(ZW*U0 + ZWN*U0*EPS)
      A(3,4) = -MASS*V0-MASS*XG*R0+2*MASS*ZG*P0+ RHO/2*L**4*(2*ZPP*
     .         P0 + ZPR*R0) + RHO/2*L**3*ZVP*V0
      A(3,5) = MASS*U0 - MASS*YG*R0+2*MASS*ZG*Q0+RHO/2*L**3*ZQ*U0 +
     .         RHO/2*L**3*ZQN*U0*EPS
      A(3,6) =-MASS*XG*P0-MASS*YG*Q0+RHO/2*L**4*(ZPR*P0+2*ZRR*R0)+
```

FILE: TX DSL A1

```
              RHO/2*L**3*ZVR*V0
     A(3,10)= -(WEIGHT - BOY)*COS(THETA0)*SIN(PHI0)
     A(3,11)= -(WEIGHT - BOY)*SIN(THETA0)*COS(PHI0)
*
     A(4,1) = MASS*YG*Q0 + MASS*ZG*R0 + RHO/2*L**4*(KP*P0 + ...
              KR*R0)+RHO/2*L**3*(KV*V0+2*U0*(KDB/2*DBP-KDB/2*DBS))+...
              RHO/2*L**3*U0*KPROP+ RHO/2*L**4*KPN*P0*EPS
     A(4,2) = -MASS*YG*P0 + RHO/2*L**4*KVQ*Q0 + RHO/2*L**2*(KV*U0...
              + KVW*W0)
     A(4,3) = -MASS*ZG*P0 + RHO/2*L**4*(KWP*P0 + KWR*R0) + ...
              RHO/2*L**3*KVW*V0
     A(4,4) = -IXY*R0 + IXZ*Q0 - MASS*YG*V0 - MASS*ZG*W0 + ...
              RHO/2*L**5*KPQ*Q0 + RHO/2*L**4*(KP*U0+KWP*W0)
     A(4,5) = -IZ*R0 + IY*R0 + 2*IYZ*Q0 + IXZ*P0 + MASS*YG*U0 +...
              RHO/2*L**5*(KPQ*P0 + KQR*R0) + RHO/2*L**4*KVQ*V0
     A(4,6) = -IZ*Q0 + IY*Q0 - 2*IYZ*R0 + MASS*ZG*U0 + ...
              RHO/2*L**5*KQR*Q0 + RHO/2*L**4*(KR*U0+KWR*W0)
     A(4,10)= -(YG*WEIGHT-YB*BOY)*COS(THETA0)*SIN(PHI0)...
              -(ZG*WEIGHT-ZB*BOY)*COS(THETA0)*COS(PHI0)
     A(4,11)= -(YG*WEIGHT-YB*BOY)*SIN(THETA0)*COS(PHI0)...
              +(ZG*WEIGHT-ZB*BOY)*SIN(THETA0)*SIN(PHI0)
*
     A(5,1) = -MASS*XG*Q0 + RHO/2*L**4*MQ*Q0 + RHO/2*L**3*MW*W0 +...
              RHO/2*L**3*U0*(MDS*DS+MDB/2*DBP) + RHO/2*L**4*MQN*Q0*...
              EPS + RHO/2*L**3*(MWN*W0 + 2*MDSN*U0*DS)*EPS+...
              RHO/2*L**3*U0*MDB/2*DBS
     A(5,2) = MASS*XG*P0 + MASS*ZG*R0 + RHO/2*L**4*(MVP*P0 + ...
              MVR*R0) + RHO*L**3*MVV*V0
     A(5,3) = -MASS*ZG*Q0 + RHO/2*L**3*MW*U0 + RHO/2*L**3*MWN*U0*EPS
     A(5,4) = -IX*R0 + IZ*R0 - IYZ*Q0 - 2*IXZ*P0 + MASS*XG*V0 + ...
              RHO/2*L**5*(2*MPP*P0 + MPR*R0) + RHO/2*L**4*MVP*V0
     A(5,5) = IXY*R0 -IYZ*P0 - MASS*XG*U0 -MASS*ZG*W0 + RHO/2*...
              L**4*MQ*U0 + RHO/2*L**4*MQN*U0*EPS
     A(5,6) = -IX*P0 + IZ*P0 + IXY*Q0 + 2*IXZ*R0 + MASS*ZG*V0 +...
              RHO/2*L**5*(MPR*P0+2*MRR*R0)+RHO/2*L**4*MVR*V0
     A(5,10)= (XG*WEIGHT-XB*BOY)*COS(THETA0)*SIN(PHI0)
     A(5,11)= (XG*WEIGHT-XB*BOY)*SIN(THETA0)*COS(PHI0) - ...
              (ZG*WEIGHT-ZB*BOY)*COS(THETA0)
*
     A(6,1) = -MASS*XG*R0 + RHO/2*L**4*(NP*P0 +NR*R0) + RHO/2*...
              L**3*(NV*V0+2*NDR*U0*DR)+RHO*L**3*U0*NPROP
     A(6,2) = -MASS*YG*R0 + RHO/2*L**4*NVQ*Q0 + RHO/2*L**3*(NV*U0+...
              NVW*W0)
     A(6,3) = MASS*XG*P0 + MASS*YG*Q0 + RHO/2*L**4*(NWP*P0+NWR*R0)+...
              RHO/2*L**3*NVW*V0
     A(6,4) = -IY*Q0 + IX*Q0 + 2*IXY*P0 +IYZ*R0 + MASS*XG*W0+...
              RHO/2*L**5*NPQ*Q0 + RHO/2*L**4*(NP*U0+NWP*W0)
     A(6,5) = -IY*P0 + IX*P0 - 2*IXY*Q0 - IXZ*R0 + MASS*YG*W0+...
              RHO/2*L**5*(NPQ*P0+NQR*R0) + RHO/2*L**4*NVQ*V0
     A(6,6) = IYZ*P0 -IXZ*Q0 - MASS*XG*U0 -MASS*YG*V0 + ...
              RHO/2*L**5*NQR*Q0 + RHO/2*L**4*(NR*U0 +NWR*W0)
     A(6,10)= (XG*WEIGHT-XB*BOY)*COS(THETA0)*COS(PHI0)
     A(6,11)= -(XG*WEIGHT-XB*BOY)*SIN(THETA0)*SIN(PHI0) +...
              (YG*WEIGHT-YB*BOY)*COS(THETA0)
```

```
*
      A(7,1) = COS(PSI0)*COS(THETA0)
      A(7,2) = COS(PSI0)*SIN(THETA0)*SIN(PHI0) - SIN(PSI0)*COS(PHI0)
      A(7,3) = COS(PSI0)*SIN(THETA0)*COS(PHI0) + SIN(PSI0)*SIN(PHI0)
      A(7,10)= V0*COS(PSI0)*SIN(THETA0)*COS(PHI0) + V0*SIN(PSI0)*...
               SIN(PHI0) - W0*COS(PSI0)*SIN(THETA0)*SIN(PHI0) + ...
               W0*SIN(PSI0)*COS(PHI0)
      A(7,11)= -U0*COS(PSI0)*SIN(THETA0) + V0*COS(PSI0)*COS(THETA0)*...
               SIN(PHI0) + W0*COS(PSI0)*COS(THETA0)*COS(PHI0)
      A(7,12)= -U0*SIN(PSI0)*COS(THETA0) - V0*SIN(PSI0)*SIN(THETA0)*...
               SIN(PHI0) - V0*COS(PSI0)*COS(PHI0) - W0*SIN(PSI0)*...
               SIN(THETA0)*SIN(PHI0) + W0*COS(PSI0)*SIN(PHI0)
*
      A(8,1) = SIN(PSI0)*COS(THETA0)
      A(8,2) = SIN(PSI0)*SIN(THETA0)*SIN(PHI0) + COS(PSI0)*COS(PHI0)
      A(8,3) = SIN(PSI0)*SIN(THETA0)*COS(PHI0) - COS(PSI0)*SIN(PHI0)
      A(8,10)= V0*SIN(PSI0)*SIN(THETA0)*COS(PHI0) - V0*COS(PSI0)*...
               SIN(PHI0) - W0*SIN(PSI0)*SIN(THETA0)*SIN(PHI0) - ...

               W0*COS(PSI0)*COS(PHI0)
      A(8,11)= -U0*SIN(PSI0)*SIN(THETA0) + V0*SIN(PSI0)*COS(THETA0)*...
               SIN(PHI0) + W0*SIN(PSI0)*COS(THETA0)*COS(PHI0)
      A(8,12)= U0*COS(PSI0)*COS(THETA0) + V0*COS(PSI0)*SIN(THETA0)*...
               SIN(PHI0) - V0*SIN(PSI0)*COS(PHI0) + W0*COS(PSI0)*...
               SIN(THETA0)*COS(PHI0) + W0*SIN(PSI0)*SIN(PHI0)
*
      A(9,1) = -SIN(THETA0)
      A(9,2) = COS(THETA0)*SIN(PHI0)
      A(9,3) = COS(THETA0)*COS(PHI0)
      A(9,10)= V0*COS(THETA0)*COS(PHI0)-W0*COS(THETA0)*SIN(PHI0)
      A(9,11)= -U0*COS(THETA0)-V0*SIN(THETA0)*SIN(PHI0) -...
                W0*SIN(THETA0)*COS(PHI0)
*
      A(10,4) = 1.0
      A(10,5) = SIN(PHI0)*TAN(THETA0)
      A(10,6) = COS(PHI0)*TAN(THETA0)
      A(10,10)= Q0*COS(PHI0)*TAN(THETA0) - R0*SIN(PHI0)*TAN(THETA0)
      A(10,11)= Q0*SIN(PHI0)/COS(THETA0)*1.0/COS(THETA0) + ...
                R0*COS(PHI0)/COS(THETA0)*1.0/COS(THETA0)
*
      A(11,5) = COS(PHI0)
      A(11,6) = -SIN(PHI0)
      A(11,10)= -Q0*SIN(PHI0) - R0*COS(PHI0)
*
      A(12,5) = SIN(PHI0)/COS(THETA0)
      A(12,6) = COS(PHI0)/COS(THETA0)
      A(12,10)= Q0*COS(PHI0)/COS(THETA0)-R0*SIN(PHI0)/COS(THETA0)
      A(12,11)= Q0*SIN(PHI0)/COS(THETA0)*TAN(THETA0) + ...
                R0*COS(PHI0)/COS(THETA0)*TAN(THETA0)
*
*     WRITE(10,200)((A(I,J),J=1,12),I=1,12)
*
```

```
*     CALCULATE THE B MATRIX
*
*
       B(1,1) = RHO/2*L**3*XRDR*U0*R0+RHO/2*L**2*(XRDR*U0*V0+U0**2*...
                2*XDRDR*DR)
       B(1,2) = U0*Q0*XQDB/2 + U0*W0*XWDB/2 + U0**2*XDBDB*DBS
       B(1,3) = U0*Q0*XQDB/2 + U0*W0*XWDB/2 + U0**2*XDBDB*DBP
       B(1,4) = U0*Q0*XQDS + U0*W0*XWDS +U0**2*2*XDSDS*DS+RHO/2*L**3*...
                XQDSN*U0*Q0*EPS + RHO/2*L**2*(XWDSN*U0*W0 + 2*XDSDSN*...
                U0**2*DS)*EPS
       B(1,5) = RHO/2*L**2*0.12*CD0*0.12*RPM
       B(1,6) = SIN(THETA0)
*
       B(2,1) = RHO/2*L**2*YDR*U0**2
       B(2,6) = -COS(THETA0)*SIN(PHI0)
*
       B(3,2) = U0**2*ZDB/2*RHO/2*L**2
       B(3,3) = U0**2*ZDB/2*RHO/2*L**2
       B(3,4) = U0**2*ZDS*RHO/2*L**2 + RHO/2*L**2*ZDSN*U0**2*EPS
       B(3,6) = -COS(THETA0)*COS(PHI0)
*
       B(4,2) =-RHO/2*L**3*U0**2*KDB/2
       B(4,3) = RHO/2*L**3*U0**2*KDB/2
       B(4,6) = -YB*COS(THETA0)*COS(PHI0) + ZB*COS(THETA0)*SIN(PHI0)
*
       B(5,2) = RHO/2*L**3*U0**2*MDB/2
       B(5,3) = RHO/2*L**3*U0**2*MDB/2
       B(5,4) = RHO/2*L**3*(U0**2*MDS+MDSN*U0**2*EPS)
       B(5,6) = XB*COS(THETA0)*COS(PHI0) + ZB*SIN(THETA0)
*
       B(6,1) = RHO/2*L**3*NDR*U0**2
       B(6,6) = -XB*COS(THETA0)*SIN(PHI0) - YB*SIN(THETA0)
*
*     FORMULATE THE A AND B MATRIX FOR STATE SPACE REPRESENTATION
*
*     MULTIPLY MMINV AND DF/DX
*
       DO 80 I = 1,6
          DO 70 J = 1,6
```

FILE: TX   DSL   A1

```
              SUM = 0.0
              DO 60 K = 1,6
              SUM = SUM + MMINV(I,K)*A(K,J)
60            CONTINUE
              AA(I,J) = SUM
70         CONTINUE
80      CONTINUE
*
*
*       MULTIPLY MMINV AND DF/DZ
*
*
        DO 50 I = 1,6
           DO 40 J = 7,12
           SUM = 0.0
               DO 30 K = 1,6
               SUM = SUM + MMINV(I,K)*A(K,J)
30             CONTINUE
               AA(I,J) = SUM
40         CONTINUE
50      CONTINUE
*
*
        DO 5 I = 7,12
           DO 6 J = 1,12
           AA(I,J) = A(I,J)
6          CONTINUE
5       CONTINUE
*
*
        WRITE(10,200)((AA(I,J),J=1,12),I=1,12)
200     FORMAT( 6E12.4)
*
*
*       MULTIPLY MMINV AND DF/DU
*
*
        DO 110 I = 1,6
           DO 100 J = 1,6
              SUM = 0.0
              DO 90 K = 1,6
              SUM = SUM + MMINV(I,K)*B(K,J)
90            CONTINUE
              BB(I,J) = SUM
100        CONTINUE
110     CONTINUE
*
*
        WRITE( 9,300)((BB(I,J),J=1,6),I=1,6)
300     FORMAT(6E12.4)
*
*
        DO 405 I = 1,6
        READ (2,401)(GKK(I,J), J=1,21)
405     WRITE(3,401)(GKK(I,J), J=1,21)
401     FORMAT(3E20.10)
*
```

```
*
      ELSE
      END IF
*
      CALL DADS(INFO,ISTRAT,IOPT,IONED,IPRINT,IGRAD,NDV,NCON,DX,...
              VLB,VUB,OBJ,GW,IDG,NGT,IC,DF,AW,NRA,NCOLA,WK,NRWK,...
              IWK,NRIWK)
      IF (INFO.EQ. 0) DELPRT=0.2
*
DERIVATIVE
NOSORT
*
*
      LATYAW = 0.0
      NORPIT = 0.0

*
*****LINEAR MODEL*****************************************************
*
*
*    CALCULATE BB*U  PART OF XDOT = AA*X + BB*U
*
      DO 10 J = 1,6
         SUM = 0.0
         DO 15 K = 1,6
            SUM = SUM + BB(J,K)*UMOD(K)
15       CONTINUE
         XDOTU(J) = SUM
10    CONTINUE
*  CALCULATE AA*X
      DO 21 J= 1,12
         SUM = 0.0
         DO 25 K = 1,12
            SUM = SUM + AA(J,K)*X(K)
25       CONTINUE
         XDOTX(J) = SUM
21    CONTINUE
*  CALCULATE XDOT = AA*X + BB*U
      DO 31 J = 1,6
         XDOT(J) = XDOTX(J) + XDOTU(J)
31    CONTINUE
      DO 35 J = 7,12
         XDOT(J) = XDOTX(J)
35    CONTINUE
*
      UDOTM = XDOT(1)
      VDOTM = XDOT(2)
      WDOTM = XDOT(3)
      PDOTM = XDOT(4)
      QDOTM = XDOT(5)
      RDOTM = XDOT(6)
      XDOTM = XDOT(7)
      YDOTM = XDOT(8)
      ZDOTM = XDOT(9)
      PHMDOT= XDOT(10)
      THETMD= XDOT(11)
      PSMDOT= XDOT(12)
*     WRITE(8,600)
*   INTEGRATE XDOT TO GET THE STATE VECTOR X
```

```
*
      UM =INTGRL(6.0, UDOTM)
      VM= INTGRL(0.0, VDOTM)
      WM= INTGRL(0.0, WDOTM)
      PM= INTGRL(0.0, PDOTM)
      QM= INTGRL(0.0, QDOTM)
      RM= INTGRL(0.0, RDOTM)
      XPOSM = INTGRL(0.0, XDOTM)
      YPOSM = INTGRL(0.0, YDOTM)
      ZPOSM = INTGRL(0.0, ZDOTM)
      PHIM = INTGRL(0.0, PHMDOT)
      THETAM = INTGRL(0.0, THETMD)
      INTGRD = (UM*UM+VM*VM+WM*WM+PM*PM+QM*QM+RM*RM+...
               XPOSM*XPOSM+(YPOSM-YORD)*(YPOSM-YORD)+...
               (ZPOSM-ORDDEP)*(ZPOSM-ORDDEP)+ PHIM*PHIM+...
               THETAM*THETAM+PSIM*PSIM) + (DSM*DSM+DBSM*DBSM)+...
               (DBPM*DBPM)+(DRM*DRM)
      OBJ1 = INTGRL(0.,(0.5)*INTGRD)
      OBJ = OBJ1
      PSIM = INTGRL(0.0, PSMDOT)
*
*
      X(1) = UM
      X(2) = VM
      X(3) = WM
      X(4) = PM
      X(5) = QM
      X(6) = RM
      X(7) = XPOSM
      X(8) = YPOSM
      X(9) = ZPOSM
      X(10) = PHIM
      X(11) = THETAM
      X(12) = PSIM
*
*     ZDEPTH = ZORD - X(9)
      THMANG = X(11)*57.3
      UMOD(1)=DRM
      UMOD(2) = DBSM
      UMOD(3) =DBPM
      UMOD(4) = DSM
      UMOD(5) = DRPM
      UMOD(6) = DBOY
*
      PHANG=PHIM/0.0174532925
      THMANG=THETAM/0.0174532925
      PSMANG= PSIM/ 0.0174532925
      PITCHM=THMANG
```

```
*
******CONTROL LAW*****************************************************
*
*
      DBS = UMOD(2)
      DBP = UMOD(3)
      DS  = UMOD(4)
      DR  = UMOD(1)
*     DBS = -(GKK(2,1)*U + GKK(2,2)*V + GKK(2,3)*W + GKK(2,4)*P +...
*           GKK(2,5)*Q + GKK(2,6)*R + GKK(2,7)*XPOS + GKK(2,8)*YPOS +...
*           GKK(2,9)*ZPOS + GKK(2,10)*PHI + GKK(2,11)*THETA +  ...
*           GKK(2,12)*PSI + GKK(2,13)*WM + GKK(2,14)*QM + GKK(2,15)*...
*           ZPOSM + GKK(2,16)*THETAM + GKK(2,17)*UMOD(2) + GKK(2,18)*...
*           UMOD(3) + GKK(2,19)*UMOD(4))
*     DBP = -(GKK(3,1)*U + GKK(3,2)*V + GKK(3,3)*W + GKK(3,4)*P +...
*           GKK(3,5)*Q + GKK(3,6)*R + GKK(3,7)*XPOS + GKK(3,8)*YPOS +...
*           GKK(3,9)*ZPOS + GKK(3,10)*PHI + GKK(3,11)*THETA +  ...
*           GKK(3,12)*PSI + GKK(3,13)*WM + GKK(3,14)*QM + GKK(3,15)*...
*           ZPOSM + GKK(3,16)*THETAM + GKK(3,17)*UMOD(2) + GKK(3,18)*...
*           UMOD(3) + GKK(3,19)*UMOD(4))
*     DS  = -(GKK(4,1)*U + GKK(4,2)*V + GKK(4,3)*W + GKK(4,4)*P +...
*           GKK(4,5)*Q + GKK(4,6)*R + GKK(4,7)*XPOS + GKK(4,8)*YPOS +...
*           GKK(4,9)*ZPOS + GKK(4,10)*PHI + GKK(4,11)*THETA +  ...
*           GKK(4,12)*PSI + GKK(4,13)*WM + GKK(4,14)*QM + GKK(4,15)*...
*           ZPOSM + GKK(4,16)*THETAM + GKK(4,17)*UMOD(2) + GKK(4,18)*...
*           UMOD(3) + GKK(4,19)*UMOD(4))

*     PUT IN STERN AND BOW PLANE STOPS
*
*     IF(ABS(DBS).GT.0.6) THEN
*       DBS = 0.6*ABS(DBS)/DBS
*     ENDIF
*     IF(ABS(DBP).GT.0.6) THEN
*       DBP = 0.6*ABS(DBP)/DBP
*     ENDIF
*     IF(ABS(DS).GT.0.6) THEN
*       DS = 0.6*ABS(DS)/DS
*     ENDIF
*
******NON-LINEAR MODEL***********************************************
*
*     PROPULSION MODEL
*
*
      SIGNU = 1.0
      IF (U.LT.0.0) SIGNU = -1.0
      IF (ABS(U).LT.X1TEST) U = X1TEST
      SIGNN = 1.0
      IF (RPM.LT.0.0) SIGNN = -1.0
      ETA = 0.012*RPM/U
```

|

```
FILE: TX        DSL       A1

      RE = U*L/NU
      CD0 =  .00385 + (1.296E-17)*(RE - 1.2E7)**2
      CT  = 0.008*L**2*ETA*ABS(ETA)/(A0)
      CT1 = 0.008*L**2/(A0)
      EPS = -1.0+SIGNN/SIGNU*(SQRT(CT+1.0)-1.0)/(SQRT(CT1+1.0)-1.0)
      XPROP = CD0*(ETA*ABS(ETA) - 1.0)
*
*
*
*     CALCULATE THE DRAG FORCE, INTEGRATE THE DRAG OVER THE VEHICLE
*     INTEGRATE USING A 4 TERM GAUSS QUADUTURE
*
*
      LATYAW = 0.0
      NORPIT = 0.0
      DO 500 K = 1,4
         UCF(K) = SQRT((V+G4(K)*R*L)**2 + (W-G4(K)*Q*L)**2)
         IF(UCF(K).GT.1E-10) THEN
         TERM0  = (RHO/2)*(CDY*HH(K)*(V+G4(K)*R*L)**2 +...
                  CDZ*BR(K)*(W-G4(K)*Q*L)**2)
         TERM1  = TERM0*(V+G4(K)*R*L)/UCF(K)
         TERM2  = TERM0*(W-G4(K)*Q*L)/UCF(K)
         LATYAW = LATYAW + TERM1*GK4(K)*L
         NORPIT = NORPIT + TERM2*GK4(K)*L
         END IF
500   CONTINUE
*
*
*     FORCE EQUATIONS
*
*
*    LONGITUDINAL FORCE
*
      FP(1) = MASS*V*R - MASS*W*Q + MASS*XG*Q**2 + MASS*XG*R**2-...
             MASS*YG*P*Q - MASS*ZG*P*R + (RHO/2)*L**4*(XPP*P**2 +...
             XQQ*Q**2 + XRR*R**2 + XPR*P*R) +(RHO/2)*L**3*(XWQ*W*Q +...
             XVP*V*P+XVR*V*R+U*Q*(XQDS*DS+XQDB/2*DBP)+XRDR*U*R*DR)+...
             (RHO/2)*L**2*(XVV*V**2 + XWW*W**2 + XVDR*U*V*DR + U*W*...
             (XWDS*DS+XWDB/2*DBP)+U**2*(XDSDS*DS**2+XDBDB/2*DBP**2+...
             XDRDR*DR**2))-(WEIGHT -BOY)*SIN(THETA) +(RHO/2)*L**3* ...
             XQDSN*U*Q*DS*EPS+(RHO/2)*L**2*(XWDSN*U*W*DS+XDSDSN*U**2*...
             DS**2)*EPS +(RHO/2)*L**2*U**2*XPROP+RHO/2*L**3*U*Q* ...
             XQDB/2*DBS +RHO/2*L**2*U**2*XDBDB/2*DBS**2+ ...
             RHO/2*L**2*XWDB/2*DBS*U*W
*
*    LATERAL FORCE
*
      FP(2) = -MASS*U*R + MASS*XG*P*Q + MASS*YG*R**2 - MASS*ZG*Q*R +...
             (RHO/2)*L**4*(YPQ*P*Q + YQR*Q*R)+(RHO/2)*L**3*(YP*U*P +...
             YR*U*R + YVQ*V*Q + YWP*W*P + YWR*W*R) + (RHO/2)*L**2*  ...
             (YV*U*V + YVW*V*W +YDR*U**2*DR) -LATYAW +(WEIGHT-BOY)*...
             COS(THETA)*SIN(PHI)
```

```
*
*     NORMAL FORCE
*
       FP(3) = MASS*U*Q - MASS*V*P - MASS*XG*P*R - MASS*YG*Q*R +     ...
               MASS*ZG*P**2 + MASS*ZG*Q**2 + (RHO/2)*L**4*(ZPP*P**2 +...
               ZPR*P*R + ZRR*R**2) + (RHO/2)*L**3*(ZQ*U*Q + ZVP*V*P +...
               ZVR*V*R) +(RHO/2)*L**2*(ZW*U*W + ZVV*V**2 + U**2*(ZDS*...
               DS+ZDB/2*DBP))-NORPIT+(WEIGHT-BOY)*COS(THETA)*COS(PHI)+...
               (RHO/2)*L**3*ZQN*U*Q*EPS +(RHO/2)*L**2*(ZWN*U*W +ZDSN*...
               U**2*DS)*EPS+ RHO/2*L**2*U**2*ZDB/2*DBS
*
*     ROLL FORCE
*
       FP(4) = -IZ*Q*R +IY*Q*R -IXY*P*R +IYZ*Q**2 -IYZ*R**2 +IXZ*P*Q +...
               MASS*YG*U*Q -MASS*YG*V*P -MASS*ZG*W*P+(RHO/2)*L**5*(KPQ*...
               P*Q + KQR*Q*R) +(RHO/2)*L**4*(KP*U*P +KR*U*R + KVQ*V*Q +...
               KWP*W*P + KWR*W*R) +(RHO/2)*L**3*(KV*U*V + KVW*V*W) +  ...
               (YG*WEIGHT - YB*BOY)*COS(THETA)*COS(PHI) - (ZG*WEIGHT - ...
               ZB*BOY)*COS(THETA)*SIN(PHI) + (RHO/2)*L**4*KPN*U*P*EPS +...
               (RHO/2)*L**3*U**2*KPROP +MASS*ZG*U*R+ ...

               RHO/2*L**3*U**2*(KDB/2*DBP-KDB/2*DBS)
*
*     PITCH FORCE
*
       FP(5) = -IX*P*R +IZ*P*R +IXY*Q*R -IYZ*P*Q -IXZ*P**2 +IXZ*R**2 -...
               MASS*XG*U*Q + MASS*XG*V*P + MASS*ZG*V*R - MASS*ZG*W*Q +...
               (RHO/2)*L**5*(MPP*P**2 +MPR*P*R +MRR*R**2)+(RHO/2)*L**4*...
               (MQ*U*Q + MVP*V*P + MVR*V*R) + (RHO/2)*L**3*(MW*U*W + ...
               MVV*V**2+U**2*(MDS*DS+MDB/2*DBP))+ NORPIT -(XG*WEIGHT- ...
               XB*BOY)*COS(THETA)*COS(PHI)                          +...
               (RHO/2)*L**3*(MWN*U*W+MDSN*U**2*DS)*EPS+ RHO/2*L**3*...
               U**2*MDB/2*DBS-(ZG*WEIGHT-ZB*BOY)*SIN(THETA)
*
*     YAW FORCE
*
       FP(6) = -IY*P*Q +IX*P*Q +IXY*P**2 -IXY*Q**2 +IYZ*P*R -IXZ*Q*R -...
               MASS*XG*U*R + MASS*XG*W*P - MASS*YG*V*R + MASS*YG*W*Q +...
               (RHO/2)*L**5*(NPQ*P*Q + NQR*Q*R) +(RHO/2)*L**4*(NP*U*P+...
               NR*U*R + NVQ*V*Q +NWP*W*P + NWR*W*R) +(RHO/2)*L**3*(NV*...
               U*V + NVW*V*W + NDR*U**2*DR) - LATYAW + (XG*WEIGHT -  ...
               XB*BOY)*COS(THETA)*SIN(PHI)+(YG*WEIGHT)*SIN(THETA)...
               +(RHO/2)*L**3*U**2*NPROP-YB*BOY*SIN(THETA)
*
*      IF(Z.EQ.50.0)THEN
*          WRITE (8,500)(FP(I), I = 1,6)
*          Z = 0.0
*      END IF
*
*     NOW COMPUTE THE F(1-6) FUNCTIONS
*
       DO 600 J = 1,6
               F(J) = 0.0
       DO 600 K = 1,6
               F(J) = MMINV(J,K)*FP(K) + F(J)
600    CONTINUE
*
*     THE LAST SIX EQUATIONS COME FROM THE KINEMATIC RELATIONS
*
*     FIRST SET THE DRIFT CURRENT VALUES
*
       UCO = 0.0
       VCO = 0.0
       WCO = 0.0
*
```

```
*      INERTIAL POSITION RATES F(7-9)
*
       F(7) = UCO + U*COS(PSI)*COS(THETA) + V*(COS(PSI)*SIN(THETA)*...
              SIN(PHI) - SIN(PSI)*COS(PHI)) + W*(COS(PSI)*SIN(THETA)*...
              COS(PHI) + SIN(PSI)*SIN(PHI))
*
       F(8) = VCO + U*SIN(PSI)*COS(THETA) + V*(SIN(PSI)*SIN(THETA)*...
              SIN(PHI) + COS(PSI)*COS(PHI)) + W*(SIN(PSI)*SIN(THETA)*...
              COS(PHI) - COS(PSI)*SIN(PHI))
*
       F(9) = WCO - U*SIN(THETA) +V*COS(THETA)*SIN(PHI) +W*COS(THETA)*...
              COS(PHI)
*
*      EULER ANGLE RATES F(10-12)
*
       F(10) = P + Q*SIN(PHI)*TAN(THETA) + R*COS(PHI)*TAN(THETA)
*
       F(11) = Q*COS(PHI) - R*SIN(PHI)
*
       F(12) = Q*SIN(PHI)/COS(THETA) + R*COS(PHI)/COS(THETA)

*
*
*      IF (Z.EQ.1.0)WRITE (9,500)(F(I), I = 1,12)
*00    FORMAT(6E12.4)
*      Z = Z + 1
*
*

       UDOT  = F(1)
       VDOT  = F(2)
       WDOT  = F(3)
       PDOT  = F(4)
       QDOT  = F(5)
       RDOT  = F(6)
       XDOTA= F(7)
       YDOT  = F(8)
       ZDOT  = F(9)
       PHIDOT  = F(10)
       THETAD  = F(11)
       PSIDOT  = F(12)
*
       U = INTGRL(6.0,UDOT)
       V = INTGRL(0.0,VDOT)
       W = INTGRL(0.0,WDOT)
       P = INTGRL(0.0,PDOT)
       Q = INTGRL(0.0,QDOT)
       R = INTGRL(0.0,RDOT)
       XPOS = INTGRL(0.0,XDOTA)
       YPOS = INTGRL(0.0,YDOT)
       ZPOS = INTGRL(0.0,ZDOT)
       PHI  = INTGRL(0.0,PHIDOT)
       THETA = INTGRL(0.0,THETAD)
       PSI  = INTGRL(0.0,PSIDOT)
*
       ZNEW = -ZPOS
       PHIANG = PHI/0.0174532925
       THEANG = THETA/0.0174532925
       PSIANG = PSI/0.0174532925
*
*
*
*
```

```
DYNAMIC
      RN=TIME/(FINTIM/10.-DELT/10000.)
      PN=TIME/(FINTIM/20.-DELT/10000.)
      O=INT(RN)+1
      PP=INT(PN)+1
      IF(PP.GE.20) PP=20
      IF(O.EQ.11) O=10
*
* ADDITIONALLY THE PLANES SHOULD BE AT EQUILIBRIUM SO THE
* VEHICLE WILL PROCEED AT THIS NEW DEPTH WITHIN SOME TOLERANCE
*
      DSM=DX(O)
      DBSM=DX(10+O)
      DBPM=DX(10+O)
      IF(O.GE.10) DSM=0.
      IF(O.GE.10) DBPM =0.000
      IF(O.GE.10) DBSM =0.000
      DRM=DX(20+PP)

*     RPM=DX(30+O)
*
*         CONSTRAINTS FOR A DIVE
*
*  ORDERED DEPTH = ORDDEP
      GW(1) = (ZPOSM-ORDDEP)*.5
      GW(2) = (ORDDEP-ZPOSM)*.5
*  AUV'S FINAL STATE MUST BE LEVEL FLIGHT AS FOLLOWS
      GW(3) = THETAM*10.
      GW(4) = -THETAM*10.
      GW(5)=(YPOSM-YORD)/.4
      GW(6)=(YORD-YPOSM)/.4
      GW(7) = -ZPOSM
*
*   AVOIDING THE OBSTACLE
*
*     IF (DIST1.LT.DSAVE1) DSAVE1=DIST1


*     IF (DISTV.LT.DSAVE1) DSAVEV=DISTV

*     DIST1=SQRT((XPOSM-XOBS1)*(XPOSM-XOBS1)+...
*           (ZPOSM-ZOBS1)*(ZPOSM-ZOBS1))
*     DISTV=SQRT((XPOS-XOBS1)*(XPOS-XOBS1)+...
*           (ZPOS-ZOBS1)*(ZPOS-ZOBS1))
*     GW(8) = (1.-DSAVE1)
      NDX=XPOSM/17.425
      NDZ=ZPOSM/17.425
      NDT=TIME*6./17.425
TERMINAL
      IF(INFO.EQ.0) THEN
      PRINT*,DSAVE1,DSAVEV
 9000 CONTINUE
      ELSE
      ENDIF
      IF(INFO.EQ.0) CALL ENDJOB
      CALL RERUN
*
END
STOP
```

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