

表5-2 ベクトルの回転

No.	方向余弦マトリクスによる回転			固定角型回転マトリクスによる回転		
1	$\mathbf{a}_L^I = \mathbf{D}_L^I \cdot \mathbf{a}_I^I$	◎	$\mathbf{a}_I^I = \mathbf{D}_L^{IT} \cdot \mathbf{a}_L^I$	◎	$\mathbf{a}_L^I = (\mathbf{D}_L^I)^I \cdot \mathbf{a}_I^I$	◎
2	$\mathbf{a}_L^B = \mathbf{D}_L^I \cdot \mathbf{a}_I^B$	×	$\mathbf{a}_I^A = \mathbf{D}_L^{IT} \cdot \mathbf{a}_L^A$	×	$\mathbf{a}_L^B = (\mathbf{D}_L^I)^I \cdot \mathbf{a}_I^B$	×
3	$\mathbf{a}_B^I = \mathbf{D}_B^I \cdot \mathbf{a}_L^I$	×	$\mathbf{a}_L^I = \mathbf{D}_B^{IT} \cdot \mathbf{a}_B^I$	×	$\mathbf{a}_B^I = (\mathbf{D}_B^I)^I \cdot \mathbf{a}_L^I$	◎
4	$\mathbf{a}_B^L = \mathbf{D}_B^I \cdot \mathbf{a}_L^L$	◎	$\mathbf{a}_L^L = \mathbf{D}_B^{IT} \cdot \mathbf{a}_B^L$	◎	$\mathbf{a}_B^L = (\mathbf{D}_B^I)^I \cdot \mathbf{a}_L^L$	×
5	$\mathbf{a}_A^I = \mathbf{D}_A^I \cdot \mathbf{a}_L^I$	×	$\mathbf{a}_L^I = \mathbf{D}_A^{IT} \cdot \mathbf{a}_A^I$	×	$\mathbf{a}_A^I = (\mathbf{D}_A^I)^I \cdot \mathbf{a}_L^I$	◎
6	$\mathbf{a}_A^L = \mathbf{D}_A^I \cdot \mathbf{a}_L^L$	◎	$\mathbf{a}_L^L = \mathbf{D}_A^{IT} \cdot \mathbf{a}_A^L$	◎	$\mathbf{a}_A^L = (\mathbf{D}_A^I)^I \cdot \mathbf{a}_L^L$	×
7	$\mathbf{a}_B^I = \mathbf{D}_B^I \cdot \mathbf{a}_I^I$	◎	$\mathbf{a}_I^I = \mathbf{D}_B^{IT} \cdot \mathbf{a}_B^I$	◎	$\mathbf{a}_B^I = (\mathbf{D}_B^I)^I \cdot \mathbf{a}_I^I$	◎
8	$\mathbf{a}_B^L = \mathbf{D}_B^I \cdot \mathbf{a}_I^L$	×	$\mathbf{a}_I^L = \mathbf{D}_B^{IT} \cdot \mathbf{a}_B^L$	×	$\mathbf{a}_B^L = (\mathbf{D}_B^I)^I \cdot \mathbf{a}_I^L$	×
9	$\mathbf{a}_A^I = \mathbf{D}_A^I \cdot \mathbf{a}_I^I$	◎	$\mathbf{a}_I^I = \mathbf{D}_A^{IT} \cdot \mathbf{a}_A^I$	◎	$\mathbf{a}_A^I = (\mathbf{D}_A^I)^I \cdot \mathbf{a}_I^I$	◎
10	$\mathbf{a}_A^L = \mathbf{D}_A^I \cdot \mathbf{a}_I^L$	×	$\mathbf{a}_I^L = \mathbf{D}_A^{IT} \cdot \mathbf{a}_A^L$	×	$\mathbf{a}_A^L = (\mathbf{D}_A^I)^I \cdot \mathbf{a}_I^L$	×
11	$\mathbf{a}_B^I = \mathbf{D}_B^B \cdot \mathbf{a}_I^B$	×	$\mathbf{a}_I^B = \mathbf{D}_B^{BT} \cdot \mathbf{a}_B^I$	×	$\mathbf{a}_B^I = (\mathbf{D}_B^B)^I \cdot \mathbf{a}_I^B$	◎
12	$\mathbf{a}_A^L = \mathbf{D}_A^B \cdot \mathbf{a}_B^L$	×	$\mathbf{a}_B^L = \mathbf{D}_A^{BT} \cdot \mathbf{a}_A^L$	×	$\mathbf{a}_A^L = (\mathbf{D}_A^B)^I \cdot \mathbf{a}_B^L$	×
13					$\mathbf{a}_A^L = (\mathbf{D}_A^B)^L \cdot \mathbf{a}_B^L$	◎
No.	オイラー角型四元数による回転			固定角型四元数による回転		
21	$\mathbf{a}_L^I = \mathbf{Q}_L^I \cdot \mathbf{a}_I^I \cdot \mathbf{Q}_L^{I*}$	◎	$\mathbf{a}_I^I = \mathbf{Q}_L^{I*} \cdot \mathbf{a}_L^I \cdot \mathbf{Q}_L^I$	◎	$\mathbf{a}_L^I = (\mathbf{Q}_L^I)^I \cdot \mathbf{a}_I^I \cdot (\mathbf{Q}_L^I)^{I*}$	◎
22	$\mathbf{a}_L^B = \mathbf{Q}_L^I \cdot \mathbf{a}_I^B \cdot \mathbf{Q}_L^{I*}$	×	$\mathbf{a}_I^A = \mathbf{Q}_L^{I*} \cdot \mathbf{a}_L^A \cdot \mathbf{Q}_L^I$	×	$\mathbf{a}_L^B = (\mathbf{Q}_L^I)^I \cdot \mathbf{a}_I^B \cdot (\mathbf{Q}_L^I)^{I*}$	×
23	$\mathbf{a}_B^I = \mathbf{Q}_B^I \cdot \mathbf{a}_L^I \cdot \mathbf{Q}_B^{I*}$	×	$\mathbf{a}_L^I = \mathbf{Q}_B^{I*} \cdot \mathbf{a}_B^I \cdot \mathbf{Q}_B^I$	×	$\mathbf{a}_B^I = (\mathbf{Q}_B^I)^I \cdot \mathbf{a}_L^I \cdot (\mathbf{Q}_B^I)^{I*}$	◎
24	$\mathbf{a}_B^L = \mathbf{Q}_B^I \cdot \mathbf{a}_L^L \cdot \mathbf{Q}_B^{I*}$	◎	$\mathbf{a}_L^L = \mathbf{Q}_B^{I*} \cdot \mathbf{a}_B^L \cdot \mathbf{Q}_B^I$	◎	$\mathbf{a}_B^L = (\mathbf{Q}_B^I)^I \cdot \mathbf{a}_L^L \cdot (\mathbf{Q}_B^I)^{I*}$	×
25	$\mathbf{a}_A^I = \mathbf{Q}_A^I \cdot \mathbf{a}_L^I \cdot \mathbf{Q}_A^{I*}$	×	$\mathbf{a}_L^I = \mathbf{Q}_A^{I*} \cdot \mathbf{a}_A^I \cdot \mathbf{Q}_A^I$	×	$\mathbf{a}_A^I = (\mathbf{Q}_A^I)^I \cdot \mathbf{a}_L^I \cdot (\mathbf{Q}_A^I)^{I*}$	◎
26	$\mathbf{a}_A^L = \mathbf{Q}_A^I \cdot \mathbf{a}_L^L \cdot \mathbf{Q}_A^{I*}$	◎	$\mathbf{a}_L^L = \mathbf{Q}_A^{I*} \cdot \mathbf{a}_A^L \cdot \mathbf{Q}_A^I$	◎	$\mathbf{a}_A^L = (\mathbf{Q}_A^I)^I \cdot \mathbf{a}_L^L \cdot (\mathbf{Q}_A^I)^{I*}$	×
27	$\mathbf{a}_B^I = \mathbf{Q}_B^I \cdot \mathbf{a}_I^I \cdot \mathbf{Q}_B^{I*}$	◎	$\mathbf{a}_I^I = \mathbf{Q}_B^{I*} \cdot \mathbf{a}_B^I \cdot \mathbf{Q}_B^I$	◎	$\mathbf{a}_B^I = (\mathbf{Q}_B^I)^I \cdot \mathbf{a}_I^I \cdot (\mathbf{Q}_B^I)^{I*}$	◎
28	$\mathbf{a}_B^L = \mathbf{Q}_B^I \cdot \mathbf{a}_I^L \cdot \mathbf{Q}_B^{I*}$	×	$\mathbf{a}_I^L = \mathbf{Q}_B^{I*} \cdot \mathbf{a}_B^L \cdot \mathbf{Q}_B^I$	×	$\mathbf{a}_B^L = (\mathbf{Q}_B^I)^I \cdot \mathbf{a}_I^L \cdot (\mathbf{Q}_B^I)^{I*}$	×
29	$\mathbf{a}_A^I = \mathbf{Q}_A^I \cdot \mathbf{a}_I^I \cdot \mathbf{Q}_A^{I*}$	◎	$\mathbf{a}_I^I = \mathbf{Q}_A^{I*} \cdot \mathbf{a}_A^I \cdot \mathbf{Q}_A^I$	◎	$\mathbf{a}_A^I = (\mathbf{Q}_A^I)^I \cdot \mathbf{a}_I^I \cdot (\mathbf{Q}_A^I)^{I*}$	◎
30	$\mathbf{a}_A^L = \mathbf{Q}_A^I \cdot \mathbf{a}_I^L \cdot \mathbf{Q}_A^{I*}$	×	$\mathbf{a}_I^L = \mathbf{Q}_A^{I*} \cdot \mathbf{a}_A^L \cdot \mathbf{Q}_A^I$	×	$\mathbf{a}_A^L = (\mathbf{Q}_A^I)^I \cdot \mathbf{a}_I^L \cdot (\mathbf{Q}_A^I)^{I*}$	×
31	$\mathbf{a}_A^I = \mathbf{Q}_A^B \cdot \mathbf{a}_B^I \cdot \mathbf{Q}_A^{B*}$	×	$\mathbf{a}_B^I = \mathbf{Q}_A^{B*} \cdot \mathbf{a}_A^I \cdot \mathbf{Q}_A^B$	×	$\mathbf{a}_A^I = (\mathbf{Q}_A^B)^I \cdot \mathbf{a}_B^I \cdot (\mathbf{Q}_A^B)^{I*}$	◎
32	$\mathbf{a}_A^L = \mathbf{Q}_A^B \cdot \mathbf{a}_B^L \cdot \mathbf{Q}_A^{B*}$	×	$\mathbf{a}_B^L = \mathbf{Q}_A^{B*} \cdot \mathbf{a}_A^L \cdot \mathbf{Q}_A^B$	×	$\mathbf{a}_A^L = (\mathbf{Q}_A^B)^I \cdot \mathbf{a}_B^L \cdot (\mathbf{Q}_A^B)^{I*}$	×
33					$\mathbf{a}_A^L = (\mathbf{Q}_A^B)^L \cdot \mathbf{a}_B^L \cdot (\mathbf{Q}_A^B)^{L*}$	◎

ベクトルの回転は固定角型回転マトリクスおよび固定角型四元数が利用できるが、基準の座標系が一致していなければならない。

任意のベクトルの回転は次のように、「慣性航法のアлゴリズム」に示した式(1.4-6)で表される。

$$\mathbf{b}^R = (\mathbf{D}_G^A)^R \cdot \mathbf{a}^R \quad : \text{ベクトルの回転}$$

$$\mathbf{a}_G^R = (\mathbf{D}_G^A)^R \cdot \mathbf{a}_A^R \quad : \text{座標系Rで表した座標系Aの軸ベクトルを座標系Gへ回転}$$

$\mathbf{a}^R, \mathbf{b}^R$: 座標系Rで表したベクトル

$(\mathbf{D}_G^A)^R = \mathbf{D}_G^R \cdot \mathbf{D}_A^{R^T}$: 座標系で表した座標系Aから座標系Gへの固定角型回転マトリクス

$\mathbf{D}_G^R = [\theta_1]_i \cdot [\theta_2]_j \cdots [\theta_n]_k$: 座標系RからG(座標系でなくても良い)への回転を表すオイラー角

$\mathbf{D}_A^R = [\varphi_1]_e \cdot [\varphi_2]_f \cdots [\varphi_m]_g$: 座標系RからA(座標系でなくても良い)への回転を表すオイラー角

方向余弦マトリクスでも同様に、方向余弦マトリクスの右上添え字側から右下添え字側に向かって回転される。

$$\mathbf{b}^R \xleftarrow{\mathbf{D}_G^R} \mathbf{a}^R : \text{座標系Rで表したベクトルのRからGへの回転}$$

(1) 方向余弦マトリクスによるベクトルの回転

$$\mathbf{a}_L^I = \mathbf{D}_L^I \cdot \mathbf{a}_I^I = \mathbf{D}_L^I \cdot \mathbf{D}_I^{I^T} \cdot \mathbf{a}_I^I = (\mathbf{D}_L^I)^I \cdot \mathbf{a}_I^I = \mathbf{a}_L^I$$

この方向余弦マトリクスは固定角型回転マトリクスと等しく、座標系Iで表された任意のベクトルに対し、座標系IIにおいて座標系Iから座標系Lへの回転と同じ回転を与える。ここでは回転の量が分かるように座標軸ベクトルを対象としたので右下添え字に座標系の記号を示しているが、基準の座標系が一致する任意のベクトルが回転できる。

$$\mathbf{a}_B^L = \mathbf{D}_B^L \cdot \mathbf{a}_L^L = \mathbf{D}_B^L \cdot \mathbf{D}_L^{L^T} \cdot \mathbf{a}_L^L = (\mathbf{D}_B^L)^L \cdot \mathbf{a}_L^L = \mathbf{a}_B^L$$

$$\mathbf{a}_A^L = \mathbf{D}_A^L \cdot \mathbf{a}_L^L = \mathbf{D}_A^L \cdot \mathbf{D}_L^{L^T} \cdot \mathbf{a}_L^L = (\mathbf{D}_A^L)^L \cdot \mathbf{a}_L^L = \mathbf{a}_A^L$$

$$\mathbf{a}_B^I = \mathbf{D}_B^I \cdot \mathbf{a}_I^I = \mathbf{D}_B^I \cdot \mathbf{D}_I^{I^T} \cdot \mathbf{a}_I^I = (\mathbf{D}_B^I)^I \cdot \mathbf{a}_I^I = \mathbf{a}_B^I$$

$$\mathbf{a}_A^I = \mathbf{D}_A^I \cdot \mathbf{a}_I^I = \mathbf{D}_A^I \cdot \mathbf{D}_I^{I^T} \cdot \mathbf{a}_I^I = (\mathbf{D}_A^I)^I \cdot \mathbf{a}_I^I = \mathbf{a}_A^I$$

$$\mathbf{a}_I^I = \mathbf{D}_I^I \cdot \mathbf{a}_I^I = \mathbf{D}_I^I \cdot \mathbf{D}_I^{I^T} \cdot \mathbf{a}_I^I = (\mathbf{D}_I^I)^I \cdot \mathbf{a}_I^I = \mathbf{a}_I^I$$

$$\mathbf{a}_L^L = \mathbf{D}_B^L \cdot \mathbf{a}_B^L = \mathbf{D}_L^L \cdot \mathbf{D}_B^{L^T} \cdot \mathbf{a}_B^L = (\mathbf{D}_B^L)^L \cdot \mathbf{a}_B^L = \mathbf{a}_L^L$$

$$\mathbf{a}_L^L = \mathbf{D}_A^L \cdot \mathbf{a}_A^L = \mathbf{D}_L^L \cdot \mathbf{D}_A^{L^T} \cdot \mathbf{a}_A^L = (\mathbf{D}_A^L)^L \cdot \mathbf{a}_A^L = \mathbf{a}_L^L$$

$$\mathbf{a}_I^I = \mathbf{D}_B^I \cdot \mathbf{a}_B^I = \mathbf{D}_I^I \cdot \mathbf{D}_B^{I^T} \cdot \mathbf{a}_B^I = (\mathbf{D}_B^I)^I \cdot \mathbf{a}_B^I = \mathbf{a}_I^I$$

$$\mathbf{a}_I^I = \mathbf{D}_A^I \cdot \mathbf{a}_A^I = \mathbf{D}_I^I \cdot \mathbf{D}_A^{I^T} \cdot \mathbf{a}_A^I = (\mathbf{D}_A^I)^I \cdot \mathbf{a}_A^I = \mathbf{a}_I^I$$

基準の座標系が一致していないので変換できない例。

$$\mathbf{a}_L^B = \mathbf{D}_L^I \cdot \mathbf{a}_I^B = \mathbf{D}_L^I \cdot \mathbf{D}_I^{I^T} \cdot \mathbf{a}_I^B = (\mathbf{D}_L^I)^I \cdot \mathbf{a}_I^B$$

$$\mathbf{a}_B^I = \mathbf{D}_B^L \cdot \mathbf{a}_L^I = \mathbf{D}_B^L \cdot \mathbf{D}_L^{L^T} \cdot \mathbf{a}_L^I = (\mathbf{D}_B^L)^L \cdot \mathbf{a}_L^I$$

$$\mathbf{a}_A^I = \mathbf{D}_A^L \cdot \mathbf{a}_L^I = \mathbf{D}_A^L \cdot \mathbf{D}_L^{L^T} \cdot \mathbf{a}_L^I = (\mathbf{D}_A^L)^L \cdot \mathbf{a}_L^I$$

$$\mathbf{a}_B^L = \mathbf{D}_B^I \cdot \mathbf{a}_I^L = \mathbf{D}_B^I \cdot \mathbf{D}_I^{I^T} \cdot \mathbf{a}_I^L = (\mathbf{D}_B^I)^I \cdot \mathbf{a}_I^L$$

$$\mathbf{a}_A^L = \mathbf{D}_A^I \cdot \mathbf{a}_I^L = \mathbf{D}_A^I \cdot \mathbf{D}_I^{I^T} \cdot \mathbf{a}_I^L = (\mathbf{D}_A^I)^I \cdot \mathbf{a}_I^L$$

$$\mathbf{a}_A^I = \mathbf{D}_A^B \cdot \mathbf{a}_B^I = \mathbf{D}_A^B \cdot \mathbf{D}_B^{B^T} \cdot \mathbf{a}_B^I = (\mathbf{D}_A^B)^B \cdot \mathbf{a}_B^I$$

$$\mathbf{a}_A^L = \mathbf{D}_A^B \cdot \mathbf{a}_B^L = \mathbf{D}_A^B \cdot \mathbf{D}_B^{B^T} \cdot \mathbf{a}_B^L = (\mathbf{D}_A^B)^B \cdot \mathbf{a}_B^L$$

$$\mathbf{a}_I^A = \mathbf{D}_I^L \cdot \mathbf{a}_L^A = \mathbf{D}_I^L \cdot \mathbf{D}_L^{L^T} \cdot \mathbf{a}_L^A = (\mathbf{D}_I^L)^I \cdot \mathbf{a}_L^A$$

$$\mathbf{a}_L^I = \mathbf{D}_B^L \cdot \mathbf{a}_B^I = \mathbf{D}_L^L \cdot \mathbf{D}_B^{L^T} \cdot \mathbf{a}_B^I = (\mathbf{D}_B^L)^L \cdot \mathbf{a}_B^I$$

$$\mathbf{a}_L^I = \mathbf{D}_A^L \cdot \mathbf{a}_A^I = \mathbf{D}_L^L \cdot \mathbf{D}_A^{L^T} \cdot \mathbf{a}_A^I = (\mathbf{D}_A^L)^L \cdot \mathbf{a}_A^I$$

$$\mathbf{a}_I^L = \mathbf{D}_B^I \cdot \mathbf{a}_B^L = \mathbf{D}_I^I \cdot \mathbf{D}_B^{I^T} \cdot \mathbf{a}_B^L = (\mathbf{D}_B^I)^I \cdot \mathbf{a}_B^L$$

$$\mathbf{a}_I^L = \mathbf{D}_A^I \cdot \mathbf{a}_A^L = \mathbf{D}_I^I \cdot \mathbf{D}_A^{I^T} \cdot \mathbf{a}_A^L = (\mathbf{D}_A^I)^I \cdot \mathbf{a}_A^L$$

$$\begin{aligned}\mathbf{a}_B^I &= \mathbf{D}_A^{B^T} \cdot \mathbf{a}_A^I = \mathbf{D}_B^B \cdot \mathbf{D}_A^{B^T} \cdot \mathbf{a}_A^I = (\mathbf{D}_B^A)^B \cdot \mathbf{a}_A^I \\ \mathbf{a}_B^L &= \mathbf{D}_A^{B^T} \cdot \mathbf{a}_A^L = \mathbf{D}_B^B \cdot \mathbf{D}_A^{B^T} \cdot \mathbf{a}_A^L = (\mathbf{D}_B^A)^B \cdot \mathbf{a}_A^L\end{aligned}$$

(2) 固定角型回転マトリクスによるベクトルの回転

$$\begin{aligned}\mathbf{a}_L^I &= (\mathbf{D}_L^I)^I \cdot \mathbf{a}_I^I = \mathbf{a}_L^I \\ \mathbf{a}_B^I &= (\mathbf{D}_B^I)^I \cdot \mathbf{a}_L^I = \mathbf{a}_B^I \\ \mathbf{a}_A^I &= (\mathbf{D}_A^I)^I \cdot \mathbf{a}_L^I = \mathbf{a}_A^I \\ \mathbf{a}_B^I &= (\mathbf{D}_B^I)^I \cdot \mathbf{a}_I^I = \mathbf{a}_B^I \\ \mathbf{a}_A^I &= (\mathbf{D}_A^I)^I \cdot \mathbf{a}_I^I = \mathbf{a}_A^I \\ \mathbf{a}_A^I &= (\mathbf{D}_A^B)^I \cdot \mathbf{a}_B^I = \mathbf{a}_A^I \\ \mathbf{a}_A^L &= (\mathbf{D}_A^B)^L \cdot \mathbf{a}_B^L = \mathbf{a}_A^L \\ \mathbf{a}_I^I &= (\mathbf{D}_I^I)^{I^T} \cdot \mathbf{a}_L^I = (\mathbf{D}_L^I \cdot \mathbf{D}_I^{I^T})^T \cdot \mathbf{a}_L^I = \mathbf{D}_I^I \cdot \mathbf{D}_L^{I^T} \cdot \mathbf{a}_L^I = (\mathbf{D}_I^L)^I \cdot \mathbf{a}_L^I = \mathbf{a}_I^I \\ \mathbf{a}_L^I &= (\mathbf{D}_B^I)^{I^T} \cdot \mathbf{a}_B^I = (\mathbf{D}_B^I \cdot \mathbf{D}_L^{I^T})^T \cdot \mathbf{a}_B^I = \mathbf{D}_L^I \cdot \mathbf{D}_B^{I^T} \cdot \mathbf{a}_B^I = (\mathbf{D}_L^B)^I \cdot \mathbf{a}_B^I = \mathbf{a}_L^I \\ \mathbf{a}_L^I &= (\mathbf{D}_A^I)^{I^T} \cdot \mathbf{a}_A^I = (\mathbf{D}_A^I \cdot \mathbf{D}_L^{I^T})^T \cdot \mathbf{a}_A^I = \mathbf{D}_L^I \cdot \mathbf{D}_A^{I^T} \cdot \mathbf{a}_A^I = (\mathbf{D}_L^A)^I \cdot \mathbf{a}_A^I = \mathbf{a}_L^I \\ \mathbf{a}_I^I &= (\mathbf{D}_B^I)^{I^T} \cdot \mathbf{a}_B^I = (\mathbf{D}_B^I \cdot \mathbf{D}_I^{I^T})^T \cdot \mathbf{a}_B^I = \mathbf{D}_I^I \cdot \mathbf{D}_B^{I^T} \cdot \mathbf{a}_B^I = (\mathbf{D}_I^B)^I \cdot \mathbf{a}_B^I = \mathbf{a}_I^I \\ \mathbf{a}_I^I &= (\mathbf{D}_A^I)^{I^T} \cdot \mathbf{a}_A^I = (\mathbf{D}_A^I \cdot \mathbf{D}_I^{I^T})^T \cdot \mathbf{a}_A^I = \mathbf{D}_I^I \cdot \mathbf{D}_A^{I^T} \cdot \mathbf{a}_A^I = (\mathbf{D}_I^A)^I \cdot \mathbf{a}_A^I = \mathbf{a}_I^I \\ \mathbf{a}_B^I &= (\mathbf{D}_A^B)^{I^T} \cdot \mathbf{a}_A^I = (\mathbf{D}_A^I \cdot \mathbf{D}_B^{I^T})^T \cdot \mathbf{a}_A^I = \mathbf{D}_B^I \cdot \mathbf{D}_A^{I^T} \cdot \mathbf{a}_A^I = (\mathbf{D}_B^A)^I \cdot \mathbf{a}_A^I = \mathbf{a}_B^I \\ \mathbf{a}_B^L &= (\mathbf{D}_A^B)^{L^T} \cdot \mathbf{a}_A^L = (\mathbf{D}_A^L \cdot \mathbf{D}_B^{L^T})^T \cdot \mathbf{a}_A^L = \mathbf{D}_B^L \cdot \mathbf{D}_A^{L^T} \cdot \mathbf{a}_A^L = (\mathbf{D}_B^A)^L \cdot \mathbf{a}_A^L = \mathbf{a}_B^L\end{aligned}$$

基準の座標系が一致していないので変換できない例。

$$\begin{aligned}\mathbf{a}_L^B &= (\mathbf{D}_L^I)^I \cdot \mathbf{a}_I^B \\ \mathbf{a}_B^L &= (\mathbf{D}_B^I)^I \cdot \mathbf{a}_L^L \\ \mathbf{a}_A^L &= (\mathbf{D}_A^I)^I \cdot \mathbf{a}_L^L \\ \mathbf{a}_B^L &= (\mathbf{D}_B^I)^I \cdot \mathbf{a}_I^L \\ \mathbf{a}_A^L &= (\mathbf{D}_A^I)^I \cdot \mathbf{a}_I^L \\ \mathbf{a}_A^L &= (\mathbf{D}_A^B)^I \cdot \mathbf{a}_B^L \\ \mathbf{a}_I^A &= (\mathbf{D}_L^I)^{I^T} \cdot \mathbf{a}_L^A = (\mathbf{D}_L^I \cdot \mathbf{D}_I^{I^T})^T \cdot \mathbf{a}_L^A = \mathbf{D}_I^I \cdot \mathbf{D}_L^{I^T} \cdot \mathbf{a}_L^A = (\mathbf{D}_I^L)^I \cdot \mathbf{a}_L^A \\ \mathbf{a}_L^L &= (\mathbf{D}_B^I)^{I^T} \cdot \mathbf{a}_B^L = (\mathbf{D}_B^I \cdot \mathbf{D}_L^{I^T})^T \cdot \mathbf{a}_B^L = \mathbf{D}_L^I \cdot \mathbf{D}_B^{I^T} \cdot \mathbf{a}_B^L = (\mathbf{D}_L^B)^I \cdot \mathbf{a}_B^L \\ \mathbf{a}_L^L &= (\mathbf{D}_A^I)^{I^T} \cdot \mathbf{a}_A^L = (\mathbf{D}_A^I \cdot \mathbf{D}_L^{I^T})^T \cdot \mathbf{a}_A^L = \mathbf{D}_L^I \cdot \mathbf{D}_A^{I^T} \cdot \mathbf{a}_A^L = (\mathbf{D}_L^A)^I \cdot \mathbf{a}_A^L \\ \mathbf{a}_I^L &= (\mathbf{D}_B^I)^{I^T} \cdot \mathbf{a}_B^L = (\mathbf{D}_B^I \cdot \mathbf{D}_I^{I^T})^T \cdot \mathbf{a}_B^L = \mathbf{D}_I^I \cdot \mathbf{D}_B^{I^T} \cdot \mathbf{a}_B^L = (\mathbf{D}_I^B)^I \cdot \mathbf{a}_B^L \\ \mathbf{a}_I^L &= (\mathbf{D}_A^I)^{I^T} \cdot \mathbf{a}_A^L = (\mathbf{D}_A^I \cdot \mathbf{D}_I^{I^T})^T \cdot \mathbf{a}_A^L = \mathbf{D}_I^I \cdot \mathbf{D}_A^{I^T} \cdot \mathbf{a}_A^L = (\mathbf{D}_I^A)^I \cdot \mathbf{a}_A^L \\ \mathbf{a}_B^L &= (\mathbf{D}_A^B)^{I^T} \cdot \mathbf{a}_A^L = (\mathbf{D}_A^I \cdot \mathbf{D}_B^{I^T})^T \cdot \mathbf{a}_A^L = \mathbf{D}_B^I \cdot \mathbf{D}_A^{I^T} \cdot \mathbf{a}_A^L = (\mathbf{D}_B^A)^I \cdot \mathbf{a}_A^L\end{aligned}$$

(3) オイラー角型四元数によるベクトルの回転

$$\begin{aligned}\mathbf{a}_L^I &= \mathbf{Q}_L^I \cdot \mathbf{a}_I^I \cdot \mathbf{Q}_L^{I*} = \mathbf{D}_L^I \cdot \mathbf{a}_I^I = \mathbf{D}_L^I \cdot \mathbf{D}_I^{I^T} \cdot \mathbf{a}_I^I = (\mathbf{D}_L^I)^I \cdot \mathbf{a}_I^I = \mathbf{a}_L^I \\ \mathbf{a}_B^L &= \mathbf{Q}_B^L \cdot \mathbf{a}_L^L \cdot \mathbf{Q}_B^{L*} = \mathbf{D}_B^L \cdot \mathbf{a}_L^L = \mathbf{D}_B^L \cdot \mathbf{D}_L^{L^T} \cdot \mathbf{a}_L^L = (\mathbf{D}_B^L)^L \cdot \mathbf{a}_L^L = \mathbf{a}_B^L \\ \mathbf{a}_A^L &= \mathbf{Q}_A^L \cdot \mathbf{a}_L^L \cdot \mathbf{Q}_A^{L*} = \mathbf{D}_A^L \cdot \mathbf{a}_L^L = \mathbf{D}_A^L \cdot \mathbf{D}_L^{L^T} \cdot \mathbf{a}_L^L = (\mathbf{D}_A^L)^L \cdot \mathbf{a}_L^L = \mathbf{a}_A^L \\ \mathbf{a}_B^I &= \mathbf{Q}_B^I \cdot \mathbf{a}_I^I \cdot \mathbf{Q}_B^{I*} = \mathbf{D}_B^I \cdot \mathbf{a}_I^I = \mathbf{D}_B^I \cdot \mathbf{D}_I^{I^T} \cdot \mathbf{a}_I^I = (\mathbf{D}_B^I)^I \cdot \mathbf{a}_I^I = \mathbf{a}_B^I\end{aligned}$$

$$\begin{aligned}
&= \mathbf{Q}_I^I \cdot (\mathbf{Q}_B^{I*} \cdot \mathbf{a}_B^L \cdot \mathbf{Q}_B^I) \cdot \mathbf{Q}_I^{I*} = \mathbf{D}_I^I \cdot (\mathbf{D}_B^I{}^T \cdot \mathbf{a}_B^L) = \mathbf{D}_I^I \cdot \mathbf{D}_B^I{}^T \cdot \mathbf{a}_B^L = (\mathbf{D}_I^B)^I \cdot \mathbf{a}_B^L \\
\mathbf{a}_I^L &= (\mathbf{Q}_A^I)^{I*} \cdot \mathbf{a}_A^L \cdot (\mathbf{Q}_A^I)^I = (\mathbf{Q}_A^I \cdot \mathbf{Q}_I^{I*})^* \cdot \mathbf{a}_A^L \cdot \mathbf{Q}_A^I \cdot \mathbf{Q}_I^{I*} = \mathbf{Q}_I^I \cdot \mathbf{Q}_A^{I*} \cdot \mathbf{a}_A^L \cdot \mathbf{Q}_A^I \cdot \mathbf{Q}_I^{I*} \\
&= \mathbf{Q}_I^I \cdot (\mathbf{Q}_A^{I*} \cdot \mathbf{a}_A^L \cdot \mathbf{Q}_A^I) \cdot \mathbf{Q}_I^{I*} = \mathbf{D}_I^I \cdot (\mathbf{D}_A^I{}^T \cdot \mathbf{a}_A^L) = \mathbf{D}_I^I \cdot \mathbf{D}_A^I{}^T \cdot \mathbf{a}_A^L = (\mathbf{D}_I^A)^I \cdot \mathbf{a}_A^L \\
\mathbf{a}_B^L &= (\mathbf{Q}_A^B)^{I*} \cdot \mathbf{a}_A^L \cdot (\mathbf{Q}_A^B)^I = (\mathbf{Q}_A^I \cdot \mathbf{Q}_B^{I*})^* \cdot \mathbf{a}_A^L \cdot \mathbf{Q}_A^I \cdot \mathbf{Q}_B^{I*} = \mathbf{Q}_B^I \cdot \mathbf{Q}_A^{I*} \cdot \mathbf{a}_A^L \cdot \mathbf{Q}_A^I \cdot \mathbf{Q}_B^{I*} \\
&= \mathbf{Q}_B^I \cdot (\mathbf{Q}_A^{I*} \cdot \mathbf{a}_A^L \cdot \mathbf{Q}_A^I) \cdot \mathbf{Q}_B^{I*} = \mathbf{D}_B^I \cdot (\mathbf{D}_A^I{}^T \cdot \mathbf{a}_A^L) = \mathbf{D}_B^I \cdot \mathbf{D}_A^I{}^T \cdot \mathbf{a}_A^L = (\mathbf{D}_B^A)^I \cdot \mathbf{a}_A^L
\end{aligned}$$

表5-3 ベクトルの座標変換

No.	方向余弦マトリクスによる座標変換				固定角型回転マトリクスによる座標変換			
1	$\mathbf{a}_B^I = \mathbf{D}_B^I \cdot \mathbf{a}_B^L$	◎	$\mathbf{a}_B^L = \mathbf{D}_B^{IT} \cdot \mathbf{a}_B^I$	◎	$\mathbf{a}_B^I = (\mathbf{D}_B^I)^I \cdot \mathbf{a}_B^L$	◎	$\mathbf{a}_B^L = (\mathbf{D}_B^I)^{IT} \cdot \mathbf{a}_B^I$	◎
2	$\mathbf{a}_A^I = \mathbf{D}_A^I \cdot \mathbf{a}_A^L$	◎	$\mathbf{a}_A^L = \mathbf{D}_A^{IT} \cdot \mathbf{a}_A^I$	◎	$\mathbf{a}_A^I = (\mathbf{D}_A^I)^I \cdot \mathbf{a}_A^L$	◎	$\mathbf{a}_A^L = (\mathbf{D}_A^I)^{IT} \cdot \mathbf{a}_A^I$	◎
3	$\mathbf{a}_I^L = \mathbf{D}_B^L \cdot \mathbf{a}_I^B$	◎	$\mathbf{a}_I^B = \mathbf{D}_B^{LT} \cdot \mathbf{a}_I^L$	◎	$\mathbf{a}_I^L = (\mathbf{D}_B^L)^I \cdot \mathbf{a}_I^B$	×	$\mathbf{a}_I^B = (\mathbf{D}_B^L)^{IT} \cdot \mathbf{a}_I^L$	×
4	$\mathbf{a}_L^L = \mathbf{D}_B^L \cdot \mathbf{a}_L^B$	◎	$\mathbf{a}_L^B = \mathbf{D}_B^{LT} \cdot \mathbf{a}_L^L$	◎	$\mathbf{a}_L^L = (\mathbf{D}_B^L)^I \cdot \mathbf{a}_L^B$	×	$\mathbf{a}_L^B = (\mathbf{D}_B^L)^{IT} \cdot \mathbf{a}_L^L$	×
5	$\mathbf{a}_I^L = \mathbf{D}_A^L \cdot \mathbf{a}_I^A$	◎	$\mathbf{a}_I^A = \mathbf{D}_A^{LT} \cdot \mathbf{a}_I^L$	◎	$\mathbf{a}_I^L = (\mathbf{D}_A^L)^I \cdot \mathbf{a}_I^A$	×	$\mathbf{a}_I^A = (\mathbf{D}_A^L)^{IT} \cdot \mathbf{a}_I^L$	×
6	$\mathbf{a}_L^L = \mathbf{D}_A^L \cdot \mathbf{a}_L^A$	◎	$\mathbf{a}_L^A = \mathbf{D}_A^{LT} \cdot \mathbf{a}_L^L$	◎	$\mathbf{a}_L^L = (\mathbf{D}_A^L)^I \cdot \mathbf{a}_L^A$	×	$\mathbf{a}_L^A = (\mathbf{D}_A^L)^{IT} \cdot \mathbf{a}_L^L$	×
7	$\mathbf{a}_I^I = \mathbf{D}_B^I \cdot \mathbf{a}_I^B$	◎	$\mathbf{a}_I^B = \mathbf{D}_B^{IT} \cdot \mathbf{a}_I^I$	◎	$\mathbf{a}_I^I = (\mathbf{D}_B^I)^I \cdot \mathbf{a}_I^B$	◎	$\mathbf{a}_I^B = (\mathbf{D}_B^I)^{IT} \cdot \mathbf{a}_I^I$	◎
8	$\mathbf{a}_L^I = \mathbf{D}_B^I \cdot \mathbf{a}_L^B$	◎	$\mathbf{a}_L^B = \mathbf{D}_B^{IT} \cdot \mathbf{a}_L^I$	◎	$\mathbf{a}_L^I = (\mathbf{D}_B^I)^I \cdot \mathbf{a}_L^B$	◎	$\mathbf{a}_L^B = (\mathbf{D}_B^I)^{IT} \cdot \mathbf{a}_L^I$	◎
9	$\mathbf{a}_I^I = \mathbf{D}_A^I \cdot \mathbf{a}_I^A$	◎	$\mathbf{a}_I^A = \mathbf{D}_A^{IT} \cdot \mathbf{a}_I^I$	◎	$\mathbf{a}_I^I = (\mathbf{D}_A^I)^I \cdot \mathbf{a}_I^A$	◎	$\mathbf{a}_I^A = (\mathbf{D}_A^I)^{IT} \cdot \mathbf{a}_I^I$	◎
10	$\mathbf{a}_L^I = \mathbf{D}_A^I \cdot \mathbf{a}_L^A$	◎	$\mathbf{a}_L^A = \mathbf{D}_A^{IT} \cdot \mathbf{a}_L^I$	◎	$\mathbf{a}_L^I = (\mathbf{D}_A^I)^I \cdot \mathbf{a}_L^A$	◎	$\mathbf{a}_L^A = (\mathbf{D}_A^I)^{IT} \cdot \mathbf{a}_L^I$	◎
11	$\mathbf{a}_I^B = \mathbf{D}_A^B \cdot \mathbf{a}_I^A$	◎	$\mathbf{a}_I^A = \mathbf{D}_A^{BT} \cdot \mathbf{a}_I^B$	◎	$\mathbf{a}_I^B = (\mathbf{D}_A^B)^I \cdot \mathbf{a}_I^A$	×	$\mathbf{a}_I^A = (\mathbf{D}_A^B)^{IT} \cdot \mathbf{a}_I^B$	×
12	$\mathbf{a}_L^B = \mathbf{D}_A^B \cdot \mathbf{a}_L^A$	◎	$\mathbf{a}_L^A = \mathbf{D}_A^{BT} \cdot \mathbf{a}_L^B$	◎	$\mathbf{a}_L^B = (\mathbf{D}_A^B)^I \cdot \mathbf{a}_L^A$	×	$\mathbf{a}_L^A = (\mathbf{D}_A^B)^{IT} \cdot \mathbf{a}_L^B$	×
13					$\mathbf{a}_L^B = (\mathbf{D}_A^B)^L \cdot \mathbf{a}_L^A$	×	$\mathbf{a}_L^A = (\mathbf{D}_A^B)^{LT} \cdot \mathbf{a}_L^B$	×
No.	オイラー角型四元数による座標変換				固定角型四元数による座標変換			
21	$\mathbf{a}_B^I = \mathbf{Q}_B^I \cdot \mathbf{a}_B^L \cdot \mathbf{Q}_B^{I*}$	◎	$\mathbf{a}_B^L = \mathbf{Q}_B^{I*} \cdot \mathbf{a}_B^I \cdot \mathbf{Q}_B^I$	◎	$\mathbf{a}_B^I = (\mathbf{Q}_B^I)^I \cdot \mathbf{a}_B^L \cdot (\mathbf{Q}_B^I)^{I*}$	◎	$\mathbf{a}_B^L = (\mathbf{Q}_B^I)^{I*} \cdot \mathbf{a}_B^I \cdot (\mathbf{Q}_B^I)^I$	◎
22	$\mathbf{a}_A^I = \mathbf{Q}_A^I \cdot \mathbf{a}_A^L \cdot \mathbf{Q}_A^{I*}$	◎	$\mathbf{a}_A^L = \mathbf{Q}_A^{I*} \cdot \mathbf{a}_A^I \cdot \mathbf{Q}_A^I$	◎	$\mathbf{a}_A^I = (\mathbf{Q}_A^I)^I \cdot \mathbf{a}_A^L \cdot (\mathbf{Q}_A^I)^{I*}$	◎	$\mathbf{a}_A^L = (\mathbf{Q}_A^I)^{I*} \cdot \mathbf{a}_A^I \cdot (\mathbf{Q}_A^I)^I$	◎
23	$\mathbf{a}_I^L = \mathbf{Q}_B^L \cdot \mathbf{a}_I^B \cdot \mathbf{Q}_B^{L*}$	◎	$\mathbf{a}_I^B = \mathbf{Q}_B^{L*} \cdot \mathbf{a}_I^L \cdot \mathbf{Q}_B^L$	◎	$\mathbf{a}_I^L = (\mathbf{Q}_B^L)^I \cdot \mathbf{a}_I^B \cdot (\mathbf{Q}_B^L)^{I*}$	×	$\mathbf{a}_I^B = (\mathbf{Q}_B^L)^{I*} \cdot \mathbf{a}_I^L \cdot (\mathbf{Q}_B^L)^I$	×
24	$\mathbf{a}_L^L = \mathbf{Q}_B^L \cdot \mathbf{a}_L^B \cdot \mathbf{Q}_B^{L*}$	◎	$\mathbf{a}_L^B = \mathbf{Q}_B^{L*} \cdot \mathbf{a}_L^L \cdot \mathbf{Q}_B^L$	◎	$\mathbf{a}_L^L = (\mathbf{Q}_B^L)^I \cdot \mathbf{a}_L^B \cdot (\mathbf{Q}_B^L)^{I*}$	×	$\mathbf{a}_L^B = (\mathbf{Q}_B^L)^{I*} \cdot \mathbf{a}_L^L \cdot (\mathbf{Q}_B^L)^I$	×
25	$\mathbf{a}_I^L = \mathbf{Q}_A^L \cdot \mathbf{a}_I^A \cdot \mathbf{Q}_A^{L*}$	◎	$\mathbf{a}_I^A = \mathbf{Q}_A^{L*} \cdot \mathbf{a}_I^L \cdot \mathbf{Q}_A^L$	◎	$\mathbf{a}_I^L = (\mathbf{Q}_A^L)^I \cdot \mathbf{a}_I^A \cdot (\mathbf{Q}_A^L)^{I*}$	×	$\mathbf{a}_I^A = (\mathbf{Q}_A^L)^{I*} \cdot \mathbf{a}_I^L \cdot (\mathbf{Q}_A^L)^I$	×
26	$\mathbf{a}_L^L = \mathbf{Q}_A^L \cdot \mathbf{a}_L^A \cdot \mathbf{Q}_A^{L*}$	◎	$\mathbf{a}_L^A = \mathbf{Q}_A^{L*} \cdot \mathbf{a}_L^L \cdot \mathbf{Q}_A^L$	◎	$\mathbf{a}_L^L = (\mathbf{Q}_A^L)^I \cdot \mathbf{a}_L^A \cdot (\mathbf{Q}_A^L)^{I*}$	×	$\mathbf{a}_L^A = (\mathbf{Q}_A^L)^{I*} \cdot \mathbf{a}_L^L \cdot (\mathbf{Q}_A^L)^I$	×
27	$\mathbf{a}_I^I = \mathbf{Q}_B^I \cdot \mathbf{a}_I^B \cdot \mathbf{Q}_B^{I*}$	◎	$\mathbf{a}_I^B = \mathbf{Q}_B^{I*} \cdot \mathbf{a}_I^I \cdot \mathbf{Q}_B^I$	◎	$\mathbf{a}_I^I = (\mathbf{Q}_B^I)^I \cdot \mathbf{a}_I^B \cdot (\mathbf{Q}_B^I)^{I*}$	◎	$\mathbf{a}_I^B = (\mathbf{Q}_B^I)^{I*} \cdot \mathbf{a}_I^I \cdot (\mathbf{Q}_B^I)^I$	◎
28	$\mathbf{a}_L^I = \mathbf{Q}_B^I \cdot \mathbf{a}_L^B \cdot \mathbf{Q}_B^{I*}$	◎	$\mathbf{a}_L^B = \mathbf{Q}_B^{I*} \cdot \mathbf{a}_L^I \cdot \mathbf{Q}_B^I$	◎	$\mathbf{a}_L^I = (\mathbf{Q}_B^I)^I \cdot \mathbf{a}_L^B \cdot (\mathbf{Q}_B^I)^{I*}$	◎	$\mathbf{a}_L^B = (\mathbf{Q}_B^I)^{I*} \cdot \mathbf{a}_L^I \cdot (\mathbf{Q}_B^I)^I$	◎
29	$\mathbf{a}_I^I = \mathbf{Q}_A^I \cdot \mathbf{a}_I^A \cdot \mathbf{Q}_A^{I*}$	◎	$\mathbf{a}_I^A = \mathbf{Q}_A^{I*} \cdot \mathbf{a}_I^I \cdot \mathbf{Q}_A^I$	◎	$\mathbf{a}_I^I = (\mathbf{Q}_A^I)^I \cdot \mathbf{a}_I^A \cdot (\mathbf{Q}_A^I)^{I*}$	◎	$\mathbf{a}_I^A = (\mathbf{Q}_A^I)^{I*} \cdot \mathbf{a}_I^I \cdot (\mathbf{Q}_A^I)^I$	◎
30	$\mathbf{a}_L^I = \mathbf{Q}_A^I \cdot \mathbf{a}_L^A \cdot \mathbf{Q}_A^{I*}$	◎	$\mathbf{a}_L^A = \mathbf{Q}_A^{I*} \cdot \mathbf{a}_L^I \cdot \mathbf{Q}_A^I$	◎	$\mathbf{a}_L^I = (\mathbf{Q}_A^I)^I \cdot \mathbf{a}_L^A \cdot (\mathbf{Q}_A^I)^{I*}$	◎	$\mathbf{a}_L^A = (\mathbf{Q}_A^I)^{I*} \cdot \mathbf{a}_L^I \cdot (\mathbf{Q}_A^I)^I$	◎
31	$\mathbf{a}_I^B = \mathbf{Q}_A^B \cdot \mathbf{a}_I^A \cdot \mathbf{Q}_A^{B*}$	◎	$\mathbf{a}_I^A = \mathbf{Q}_A^{B*} \cdot \mathbf{a}_I^B \cdot \mathbf{Q}_A^B$	◎	$\mathbf{a}_I^B = (\mathbf{Q}_A^B)^I \cdot \mathbf{a}_I^A \cdot (\mathbf{Q}_A^B)^{I*}$	×	$\mathbf{a}_I^A = (\mathbf{Q}_A^B)^{I*} \cdot \mathbf{a}_I^B \cdot (\mathbf{Q}_A^B)^I$	×
32	$\mathbf{a}_L^B = \mathbf{Q}_A^B \cdot \mathbf{a}_L^A \cdot \mathbf{Q}_A^{B*}$	◎	$\mathbf{a}_L^A = \mathbf{Q}_A^{B*} \cdot \mathbf{a}_L^B \cdot \mathbf{Q}_A^B$	◎	$\mathbf{a}_L^B = (\mathbf{Q}_A^B)^I \cdot \mathbf{a}_L^A \cdot (\mathbf{Q}_A^B)^{I*}$	×	$\mathbf{a}_L^A = (\mathbf{Q}_A^B)^{I*} \cdot \mathbf{a}_L^B \cdot (\mathbf{Q}_A^B)^I$	×
33					$\mathbf{a}_L^B = (\mathbf{Q}_A^B)^L \cdot \mathbf{a}_L^A \cdot (\mathbf{Q}_A^B)^{L*}$	×	$\mathbf{a}_L^A = (\mathbf{Q}_A^B)^{L*} \cdot \mathbf{a}_L^B \cdot (\mathbf{Q}_A^B)^L$	×

ベクトルの座標変換は方向余弦マトリクスまたはオイラー角型四元数を用いて、基準座標系の如何に依らず変換できる。

方向余弦マトリクスによる座標系の変換は、右下添え字側の座標系から右上添え字側の座標系へ切り替わる。座標系Gから見たベクトルを座標系Aから見たベクトルに座標変換するのは次のようになる。

$$\mathbf{a}^A = \mathbf{D}_G^A \cdot \mathbf{a}^G : \text{ベクトルの座標変換}$$

$$\mathbf{a}_L^A = \mathbf{Q}_A^{B*} \cdot \mathbf{a}_L^B \cdot \mathbf{Q}_A^B = \mathbf{D}_A^{B^T} \cdot \mathbf{a}_L^B = \mathbf{D}_B^A \cdot \mathbf{D}_L^B = \mathbf{D}_L^A = \mathbf{a}_L^A$$

(4) 固定角型四元数による座標変換

$$= \mathbf{Q}_I^I \cdot (\mathbf{Q}_A^{I*} \cdot \mathbf{a}_L^I \cdot \mathbf{Q}_A^I) \cdot \mathbf{Q}_I^{I*} = \mathbf{D}_I^I \cdot (\mathbf{D}_A^{I^T} \cdot \mathbf{a}_L^I) = \mathbf{D}_I^I \cdot \mathbf{D}_A^{I^T} \cdot \mathbf{a}_L^I = \mathbf{D}_I^A \cdot \mathbf{D}_L^I = \mathbf{D}_L^A = \mathbf{a}_L^A$$

基準の座標系が一致していないので変換できない例。

$$\mathbf{a}_L^L = (\mathbf{Q}_B^L)^I \cdot \mathbf{a}_L^B \cdot (\mathbf{Q}_B^L)^{I*} = \mathbf{Q}_B^I \cdot \mathbf{Q}_L^{I*} \cdot \mathbf{a}_L^B \cdot (\mathbf{Q}_B^I \cdot \mathbf{Q}_L^{I*})^* = \mathbf{Q}_B^I \cdot \mathbf{Q}_L^{I*} \cdot \mathbf{a}_L^B \cdot \mathbf{Q}_L^I \cdot \mathbf{Q}_B^{I*}$$

6 まとめ

6.1 座標系の回転

方向余弦マトリクスは基準座標系の如何に関わらず利用できる。他の体(非可換体)においては、それらを表現する基準の座標系と演算対象の座標軸ベクトルを表現する基準の座標系が一致していれば利用できる。

$$\mathbf{x}_B^I = \mathbf{x}_L^I \cdot \mathbf{D}_B^I \Rightarrow (\underline{x}_B^I \quad \underline{y}_B^I \quad \underline{z}_B^I) = (\underline{x}_L^I \quad \underline{y}_L^I \quad \underline{z}_L^I) \cdot \mathbf{D}_B^I : \text{方向余弦マトリクスによる座標系の回転}$$

$$\left. \begin{aligned} \underline{x}_B^I &= \mathbf{Q}_B^I \cdot \underline{x} \cdot \mathbf{Q}_B^{I*} \\ \underline{y}_B^I &= \mathbf{Q}_B^I \cdot \underline{y} \cdot \mathbf{Q}_B^{I*} \\ \underline{z}_B^I &= \mathbf{Q}_B^I \cdot \underline{z} \cdot \mathbf{Q}_B^{I*} \end{aligned} \right\} : \text{オイラー角型四元数による座標系の回転}$$

$$\mathbf{x}_B^I = (\mathbf{D}_B^I)^I \cdot \mathbf{x}_L^I \Rightarrow (\underline{x}_B^I \quad \underline{y}_B^I \quad \underline{z}_B^I) = (\mathbf{D}_B^I)^I \cdot (\underline{x}_L^I \quad \underline{y}_L^I \quad \underline{z}_L^I) : \text{固定角型回転マトリクスによる座標系の回転}$$

$$\left. \begin{aligned} \underline{x}_B^I &= (\mathbf{Q}_B^I)^I \cdot \underline{x} \cdot (\mathbf{Q}_B^I)^{I*} \\ \underline{y}_B^I &= (\mathbf{Q}_B^I)^I \cdot \underline{y} \cdot (\mathbf{Q}_B^I)^{I*} \\ \underline{z}_B^I &= (\mathbf{Q}_B^I)^I \cdot \underline{z} \cdot (\mathbf{Q}_B^I)^{I*} \end{aligned} \right\} : \text{固定角型四元数による座標系の回転}$$

6.2 ベクトルの回転

4種の体(非可換体)はいずれも基準座標系が一致していれば利用できる。

$$\mathbf{a}_B^I = \mathbf{D}_B^I \cdot \mathbf{a}_L^I : \text{方向余弦マトリクスによるベクトルの回転}$$

$$\mathbf{a}_B^I = \mathbf{Q}_B^I \cdot \mathbf{a}_L^I \cdot \mathbf{Q}_B^{I*} : \text{オイラー角型四元数によるベクトルの回転}$$

$$\mathbf{a}_B^I = (\mathbf{D}_A^B)^{I^T} \cdot \mathbf{a}_A^I : \text{固定角型回転マトリクスによるベクトルの回転}$$

$$\mathbf{a}_B^I = (\mathbf{Q}_A^B)^{I*} \cdot \mathbf{a}_A^I \cdot (\mathbf{Q}_A^B)^I : \text{固定角型四元数によるベクトルの回転}$$

6.3 ベクトルの座標変換

方向余弦マトリクスおよびオイラー角型四元数は、基準座標系の如何に関わらず利用できる。

$$\mathbf{a}_B^I = \mathbf{D}_L^I \cdot \mathbf{a}_B^L \Rightarrow \begin{pmatrix} a_{xB}^I \\ a_{yB}^I \\ a_{zB}^I \end{pmatrix} = \mathbf{D}_L^I \cdot \begin{pmatrix} a_{xB}^L \\ a_{yB}^L \\ a_{zB}^L \end{pmatrix} : \text{方向余弦マトリクスによるベクトルの座標変換}$$

$$\mathbf{a}_B^I = \mathbf{Q}_L^I \otimes \mathbf{a}_B^L \otimes \mathbf{Q}_L^{I*} \Rightarrow \begin{pmatrix} a_{xB}^I \\ a_{yB}^I \\ a_{zB}^I \end{pmatrix} = \mathbf{Q}_L^I \otimes \begin{pmatrix} 0 \\ a_{xB}^L \\ a_{yB}^L \\ a_{zB}^L \end{pmatrix} \otimes \mathbf{Q}_L^{I*} : \text{オイラー角型四元数によるベクトルの座標変換}$$

固定角型回転マトリクスおよび固定角型四元数は、それらを方向余弦マトリクスに変形し、さらにベクトルを方向余弦マトリクスと見なして一つの方向余弦マトリクスに合成できるならば、座標変換に利用できる。この体(非可換体)は座標変換に不向きであり、わざわざ利用するメリットは無い。

$$\mathbf{a}_B^I = (\mathbf{D}_L^I)^I \cdot \mathbf{a}_B^L = (\mathbf{D}_L^I \cdot \mathbf{D}_L^{I^T}) \cdot \mathbf{D}_B^L = \mathbf{D}_L^I \cdot \mathbf{D}_B^L = \mathbf{D}_B^I \cdot \mathbf{a}_B^L$$

$$\Rightarrow \begin{pmatrix} a_{xB}^I \\ a_{yB}^I \\ a_{zB}^I \end{pmatrix} = (\mathbf{D}_L^I)^I \cdot \begin{pmatrix} a_{xB}^L \\ a_{yB}^L \\ a_{zB}^L \end{pmatrix} : \text{固定角型回転マトリクスによるベクトルの座標変換}$$

$$\begin{aligned}
\mathbf{a}_B^I &= (\mathbf{Q}_L^I)^I \otimes \mathbf{a}_B^L \otimes (\mathbf{Q}_L^I)^{I*} = (\mathbf{Q}_L^I \otimes \mathbf{Q}_I^{I*}) \otimes \mathbf{a}_B^L \otimes (\mathbf{Q}_L^I \otimes \mathbf{Q}_I^{I*})^* = (\mathbf{Q}_L^I \otimes \mathbf{Q}_I^{I*}) \otimes \mathbf{a}_B^L \otimes (\mathbf{Q}_I^I \otimes \mathbf{Q}_L^{I*}) = \mathbf{Q}_L^I \otimes \mathbf{a}_B^L \otimes \mathbf{Q}_L^{I*} \\
&= \mathbf{D}_L^I \cdot \mathbf{a}_B^L = \mathbf{D}_L^I \cdot \mathbf{D}_B^L = \mathbf{D}_B^I = \mathbf{a}_B^I \\
\Rightarrow \begin{pmatrix} a_{x_B}^I \\ a_{y_B}^I \\ a_{z_B}^I \end{pmatrix} &= (\mathbf{Q}_L^I)^I \otimes \begin{pmatrix} 0 \\ a_{x_B}^L \\ a_{y_B}^L \\ a_{z_B}^L \end{pmatrix} \otimes (\mathbf{Q}_L^I)^{I*} : \text{固定角型四元数によるベクトルの座標変換}
\end{aligned}$$