

```
/*
File: Sexagesimal.cs

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Navigational Algorithms
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*/

using System;

namespace NavigationalAlgorithms
{
    public class Sexagesimal
    {
        public static double SIN( double x ) { return Math.Sin( x*Math.PI/180.0 ); }
        public static double COS( double x ) { return Math.Cos( x*Math.PI/180.0 ); }
        public static double TAN( double x ) { return Math.Tan( x*Math.PI/180.0 ); }

        public static double ASIN( double x ) { return 180.0/Math.PI*Math.Asin( x ); }
        public static double ACOS( double x ) { return 180.0/Math.PI*Math.Acos( x ); }
        public static double ATAN( double x ) { return 180.0/Math.PI*Math.Atan( x ); }
        public static double ATAN2( double x, double y) { return (180.0/Math.PI*(Math.Atan2(x,
            y))); }

        // CONVERSION DE UN ANGULO EN (°) DENTRO DE LOS LIMITES DE 0° Y 360°
        public static double ang_0_360(double ang)
        {
            if (ang < 0.0)
                while (ang < 0.0) ang = ang + 360.0;
            else if (ang > 360.0)
                while (ang > 360.0) ang = ang - 360.0;

            return (ang);
        }
    }
}
```