Besides the well-known TRIAD algorithm and the symmetric TRIAD algorithm, in which normalized sums and differences of the direction measurements are used, there is a continuum of TRIAD algorithms in which any two linearly-dependent normalized linear combination of the measurements are used. We examine in detail this "Generalized TRIAD algorithm," of which the other TRIAD algorithms are special cases and find that one, in fact, differs from the Wahba attitude solution only by terms of high order in the measurement noise.