


1) In the BS compute for each t_i
 $v_x, v_y \rightarrow \Delta x$ and Δy btw
 t_{i-1}, t_i

2) For each one t_i compute $\alpha(t_i)$
" " " " use α to rotate
 $\Delta x, \Delta y$ from
BS to IS

3) For each epoch compute x, y in 1S
as

$$x(t) = x(t-1) + \Delta x(t)$$

$$y(t) = y(t-1) + \Delta y(t)$$

$$1) \quad x(t) = x_0 + \int_{t_0}^t v(\tau) d\tau$$

constant velocity $v(\tau) = v_0 + a(t-t_0)$

$$x(t) = x_0 + v_0(t-t_0) + 1/2 a(t-t_0)^2$$

Apply to $[t-1, t]$ interval

$$x_t = x_{t-1} + v_{t-1} \Delta t + \frac{1}{2} a_t \Delta t^2$$

which a btw $i-1$ and i ?

$$\Delta_t \approx x_t - x_{t-1}$$

$$\text{2nd) } \alpha(t) = \alpha_0 + \int_{t_0}^t \omega(\tau) d\tau$$

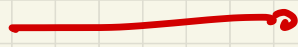
$$\omega \text{ const} \quad \longrightarrow \quad \alpha(t) = \alpha_0 + \omega(t - t_0)$$

$$\alpha_t = \alpha_{t-1} + \omega_t \Delta t$$

Rotations

$\Delta \underline{x}_{t_B}$

↑
Body



$\Delta \underline{x}_{t_I}$

↑
Inertial

$$\Delta \underline{x}_{t_I} = \begin{bmatrix} \cos(\alpha) & \sin(\alpha) \\ -\sin(\alpha) & \cos(\alpha) \end{bmatrix} \Delta \underline{x}_{t_B}$$

3)

$$x_I(t) = x_I(t-1) + \Delta x_{I,t}$$

$$y_I(t) = y_I(t-1) + \Delta y_{I,t}$$