

motion

Status

time t

position p (x_1, x_2, x_3)

velocity v (v_1, v_2, v_3)

acceleration a (a_1, a_2, a_3)

Method

$dv = a * dt$ $v[this] - v[pred] = a[this] * dt$

$dp = v * dt$ $p[this] - p[pred] = v[this] * dt$

t $t[this] = t[pred] + dt$