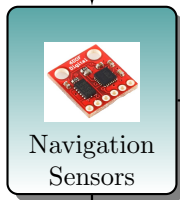


Navigation Algorithm

Explicit Complementary Filter



a_s

Sub-optimal
Vectorial Re-
construction

\hat{R}

R_y

Orientation
Observer

$\hat{\Theta}, \hat{\Omega}...$

Position
Observer

Ω_s

$a_s p_y$