

IMU CODING/DECODING

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Step 1: Initial Acceleration

- **From 0 to 20 m/s in 10 seconds:**
 - **Acceleration is constant:** $a_x = \Delta v / \Delta t = (20-0) / 10 = 2 \text{ m/s}^2$
 - **y-axis acceleration:** $a_y = 0 \text{ m/s}^2$ (no lateral movement during straight-line acceleration).

Step 2: Constant Speed (Straight Motion)

- **20 m/s for 10 seconds:**
 - Acceleration:

$$a_x = 0 \text{ m/s}^2, a_y = 0 \text{ m/s}^2$$

Step 3: Turning Motion

- **Turn radius = 100 m, constant speed = 20 m/s:**
 - **Centripetal acceleration (lateral):** $a_y = v^2 / r = 20^2 / 100 = 4 \text{ m/s}^2$
 - **Longitudinal acceleration:** $a_x = 0 \text{ m/s}^2$
 - **Angular velocity (ω):** $\omega = v / r = 20 / 100 = 0.2 \text{ rad/s}$

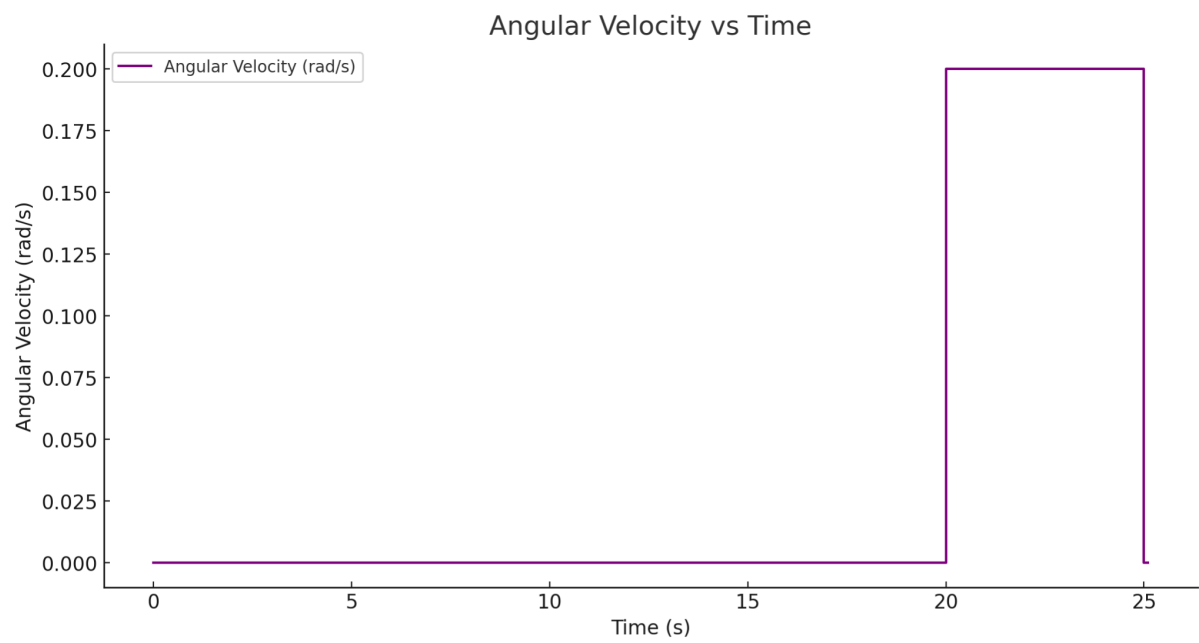
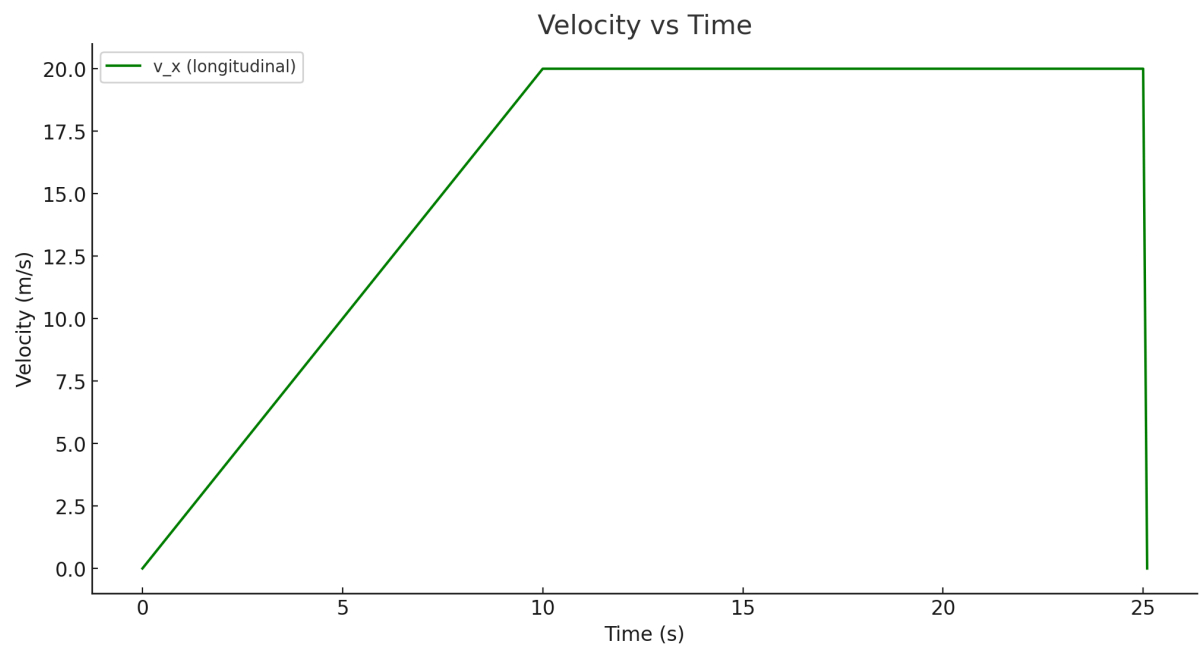
Step 4: Deceleration

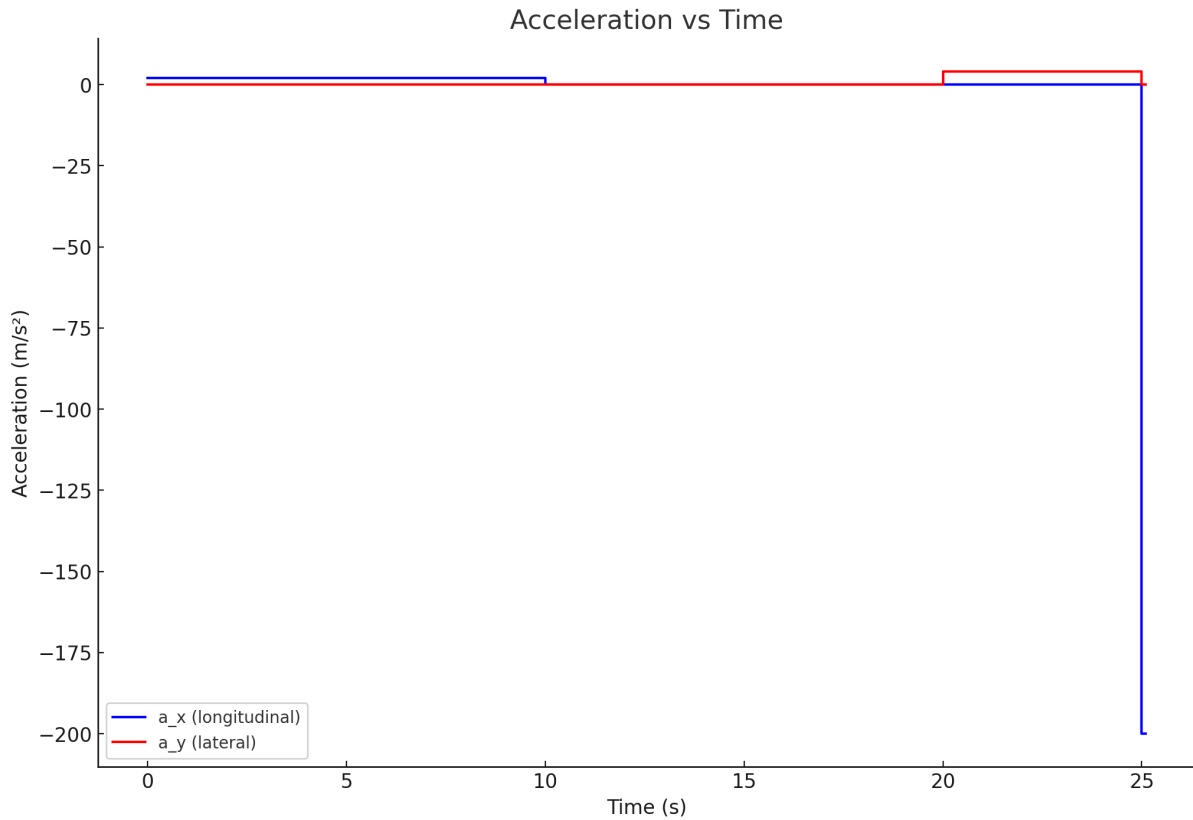
- **Stop in 1 meter:**
 - Initial speed: $v = 20 \text{ m/s}$, distance: $d = 1 \text{ m}$
 - Using: $v^2 = u^2 + 2 * a * s$

$$0 = 20^2 + 2 * a * 1$$

$$a_x = -200 \text{ m/s}^2$$

- **Time to stop:** $t = \Delta v / a = 20 / 200 = 0.1 \text{ seconds}$
- **y-axis acceleration:** $a_y = 0 \text{ m/s}^2$





The plots represent the acceleration, velocity, and angular velocity as functions of time based on the provided scenario:

1. Acceleration (x and y axes):

- Longitudinal acceleration (a_{x_xax}) starts at 2 m/s² during the initial acceleration phase, drops to 0 during constant speed and turning, and then becomes -200 m/s² during the deceleration phase.
- Lateral acceleration (a_{y_yay}) is 4 m/s² during the turn and 0 otherwise.

2. Velocity (x-axis):

- The longitudinal velocity (v_{x_xvx}) increases linearly during acceleration, remains constant at 20 m/s during both the constant speed and turning phases, and drops sharply to 0 m/s during deceleration.

3. Angular Velocity:

- The angular velocity ($\omega_{\omega\omega\omega}$) is constant at 0.2 rad/s during the turning phase and zero elsewhere.