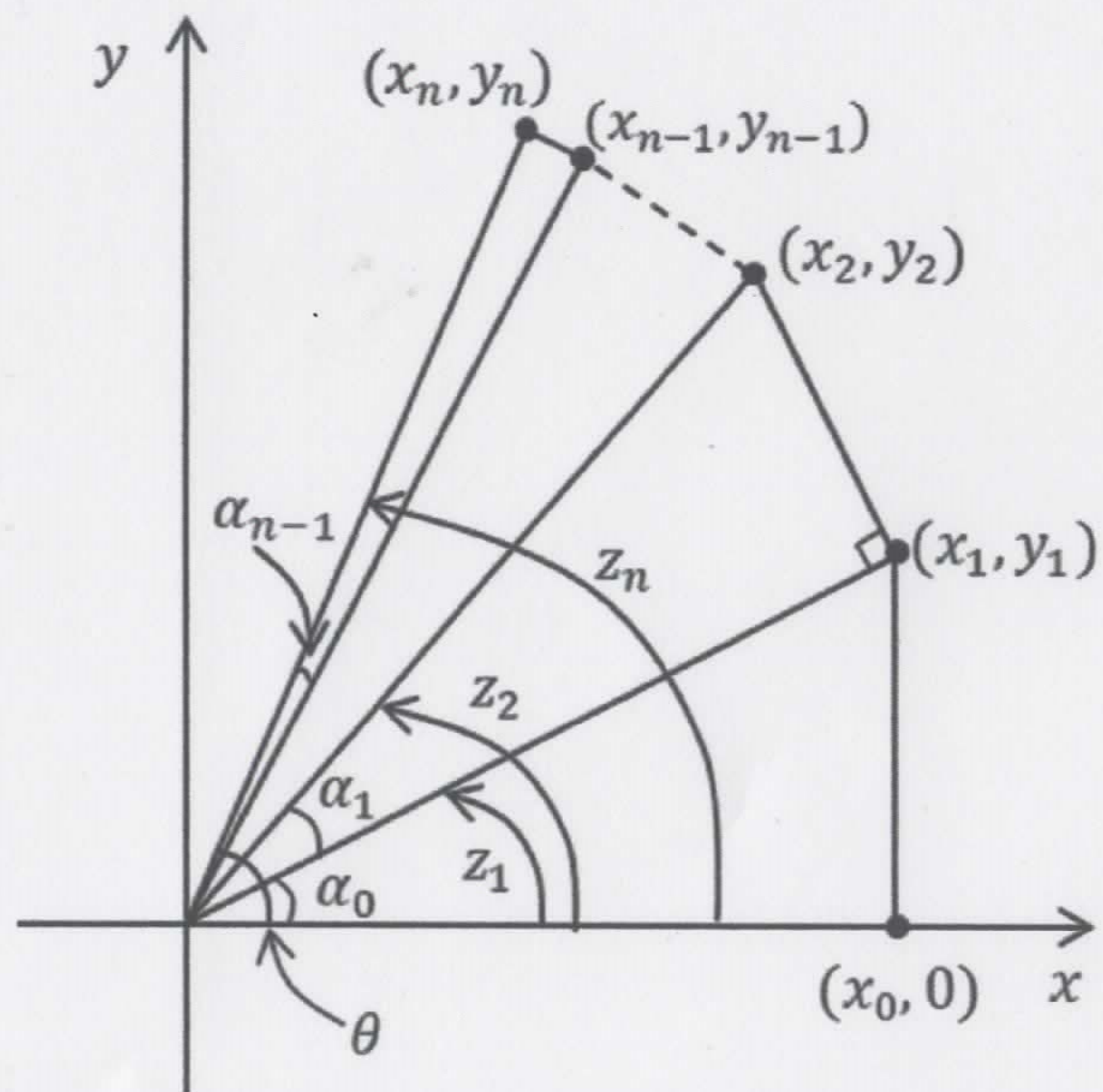


★ COPIC 法  $\equiv$   $\delta_i = \delta_i \cos \theta, \sin \theta$   $\bar{z} = \frac{z}{k}$   $\times \pi$



①  $\begin{pmatrix} x_0 \\ y_0 = 0 \end{pmatrix} \rightarrow \begin{pmatrix} x_1 \\ y_1 \end{pmatrix} \rightarrow \dots \rightarrow \begin{pmatrix} x_i \\ y_i \end{pmatrix} \rightarrow \begin{pmatrix} x_{i+1} \\ y_{i+1} \end{pmatrix} \rightarrow \dots \rightarrow \begin{pmatrix} x_m \\ y_m \end{pmatrix}$

$i=0$   
 $\delta_0 = 2^{-0} = 1$   
 $\alpha_0 = \tan^{-1} \delta_0$   
 $x_1 = x_0 - \delta_0 y_0$   
 $y_1 = y_0 + \delta_0 x_0$   
 $z_1 = z_0 + \alpha_0$

$i=i$   
 $\delta_i = 2^{-i}$   
 $\alpha_i = \tan^{-1} \delta_i$   
 $x_{i+1} = x_i - \delta_i y_i$   
 $y_{i+1} = y_i + \delta_i x_i$   
 $z_{i+1} = z_i + \alpha_i$

$i=m-1$

②  $T = T^{-1}$   $z_i > \theta$  のときは  $z_i$  を  $\frac{1}{2}$  に調整が必要

$$\alpha_i = \begin{cases} +\alpha_i & (z_i > \theta) \\ -\alpha_i & (z_i < \theta) \end{cases}$$

$$\delta_i = \begin{cases} +\delta_i & (z_i > \theta) \\ -\delta_i & (z_i < \theta) \end{cases}$$

③  $\cos \theta = \frac{x_m}{k_m x_0} = x_m$

$\sin \theta = \frac{y_m}{k_m y_0} = y_m$

$x_0 = \frac{1}{k_m}$  とすると簡単

$k_m = \sqrt{1 + \delta_0^2} \sqrt{1 + \delta_1^2} \dots \sqrt{1 + \delta_{m-1}^2} \in \mathbb{R}$  となるから  $\bar{z}$  計算可能