VOLUME = 3.0204533e+04 MM^3

SURFACE AREA = 3.0127401e+04 MM^2

AVERAGE DENSITY = 2.8832584e-05 KILOGRAM / MM^3

MASS = 8.7087474e-01 KILOGRAM

CENTER OF GRAVITY with respect to LIDAR\_ROT-FRAME coordinate frame:

X Y Z 6.0475783e-02 -8.1621602e-03 -7.2175098e+00 MM

INERTIA with respect to LIDAR\_ROT-FRAME coordinate frame: (KILOGRAM \* MM^2)

INERTIA TENSOR:

Ixx Ixy Ixz 1.5816248e+02 1.0157229e-04 -1.3176155e-02

Iyx Iyy Iyz 1.0157229e-04 1.1219941e+02 0.0000000e+00

Izx Izy Izz -1.3176155e-02 0.0000000e+00 1.7248704e+02

INERTIA at CENTER OF GRAVITY with respect to LIDAR\_ROT-FRAME coordinate frame: (KILOGRAM \* MM^2)

INERTIA TENSOR:

Ixx Ixy Ixz 1.1279642e+02 -3.2830282e-04 -3.9329952e-01

Iyx Iyy Iyz -3.2830282e-04 6.6830231e+01 5.1251186e-02

Izx Izy Izz -3.9329952e-01 5.1251186e-02 1.7248379e+02

PRINCIPAL MOMENTS OF INERTIA: (KILOGRAM \* MM^2)

I1 I2 I3 6.6830206e+01 1.1279383e+02 1.7248641e+02

ROTATION MATRIX from LIDAR\_ROT-FRAME orientation to PRINCIPAL AXES:

0.00000 -0.99998 -0.00659

1.00000 0.00000 0.00049

-0.00049 -0.00659 0.99998

ROTATION ANGLES from LIDAR\_ROT-FRAME orientation to PRINCIPAL AXES (degrees):

angles about x y z 0.000 -0.378 90.000

RADII OF GYRATION with respect to PRINCIPAL AXES:

R1 R2 R3 8.7600897e+00 1.1380591e+01 1.4073418e+01 MM

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MASS PROPERTIES OF COMPONENTS OF THE ASSEMBLY

(in assembly units and the LIDAR\_ROT-FRAME coordinate frame)

DENSITY MASS C.G.: X Y Z

PH0001A0 MATERIAL: UNKNOWN

2.88326e-05 8.70875e-01 6.04758e-02 -8.16216e-03 -7.21751e+00