Mass properties of Floating Robot 2
Configuration: Predeterminado
Coordinate system: Main Coordinate System

Mass = 5.77664482 kilograms

Total weld mass = 0.00000000 kilograms

Volume = 0.00139468 cubic meters

Surface area = 852811.79038465 square millimeters

Center of mass: (millimeters)
X = 0.00000000
Y = 0.00000000
Z = 0.00000000

Principal axes of inertia and principal moments of inertia(user-overridden): (kilograms * square millimeters)
Taken at the center of mass.
Ix = (0.99991423, 0.01201015, 0.00522297) Px = 51162.56407942
Iy = (-0.01201211, 0.99992779, 0.00034410) Py = 80953.78607720
Iz = (-0.00521846, -0.00040681, 0.99998630) Pz = 83978.54593565

Moments of inertia: (kilograms * square millimeters)
Taken at the center of mass and aligned with the output coordinate system. (Using positive tensor notation.)
Lxx = 51167.75633783 Lxy = 357.76003588 Lxz = 171.36982793
Lyx = 357.76003588 Lyy = 80949.48937923 Lyz = 3.09924817
Lzx = 171.36982793 Lzy = 3.09924817 Lzz = 83977.65037522

Moments of inertia: (kilograms * square millimeters)
Taken at the output coordinate system. (Using positive tensor notation.)
Ixx = 51167.75633783 Ixy = 357.76003588 Ixz = 171.36982793
Iyx = 357.76003588 Iyy = 80949.48937923 Iyz = 3.09924817
Izx = 171.36982793 Izy = 3.09924817 Izz = 83977.65037522

Mass Properties have been overridden at the assembly level. Therefore,
any overrides specified at the component level are ignored in
Moment of Inertia calculations. One or more components have
user-overridden mass properties that are being ignored:
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LiPo-Battery<1><Varsayılan>@Battery-with-case<1><Predeterminado>
GM3506 With Encoder@AOCS-2
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Gigabit Ethernet Port, RPi4ModelB<1><Default>@Raspberry Pi 4 Model B<1><Default>@RaspberryPi-Case<1><D
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2X USB2.0 PORTS, RPi4ModelB<1><Default>@Raspberry Pi 4 Model B<1><Default>@RaspberryPi-Case<1><Def
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