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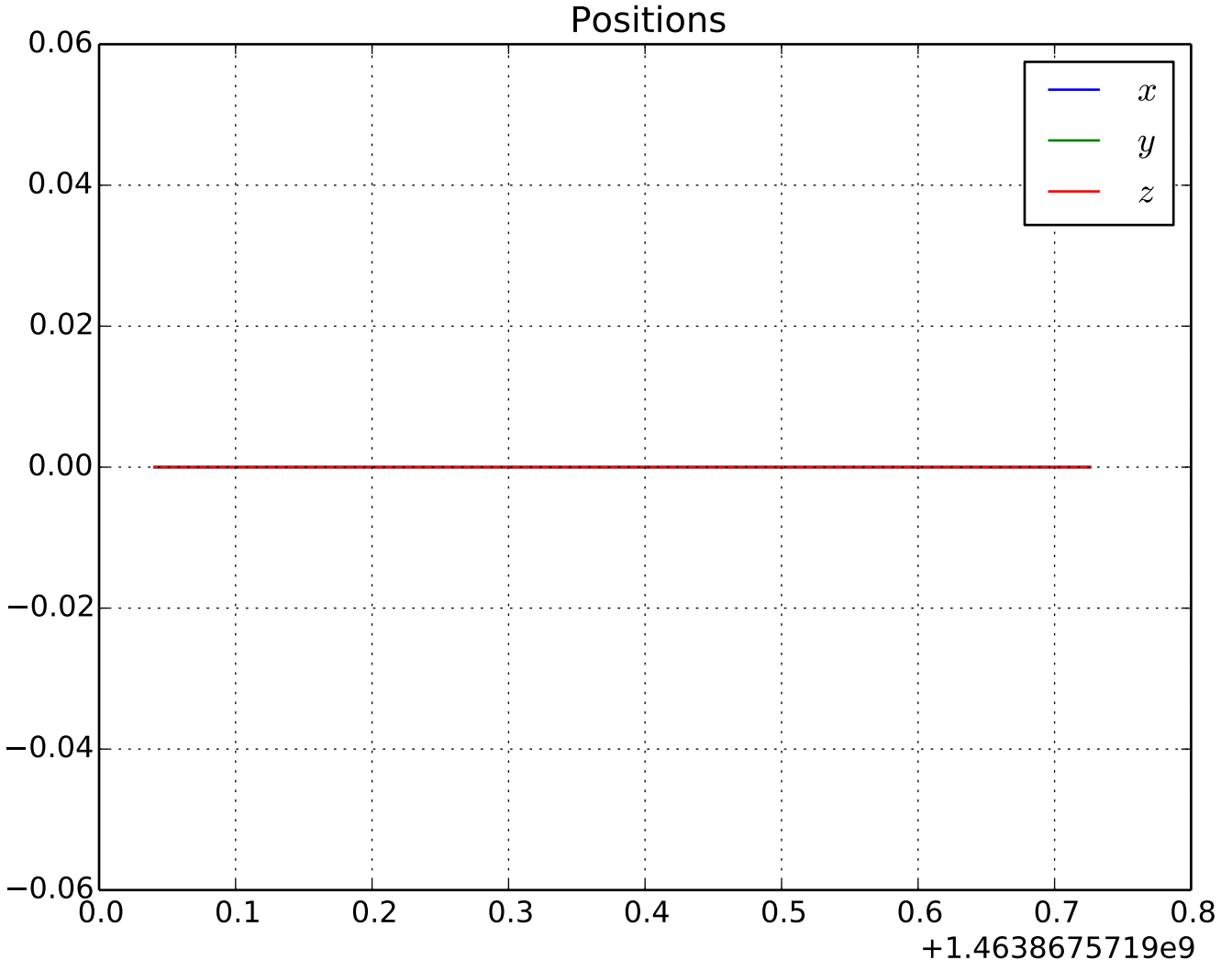
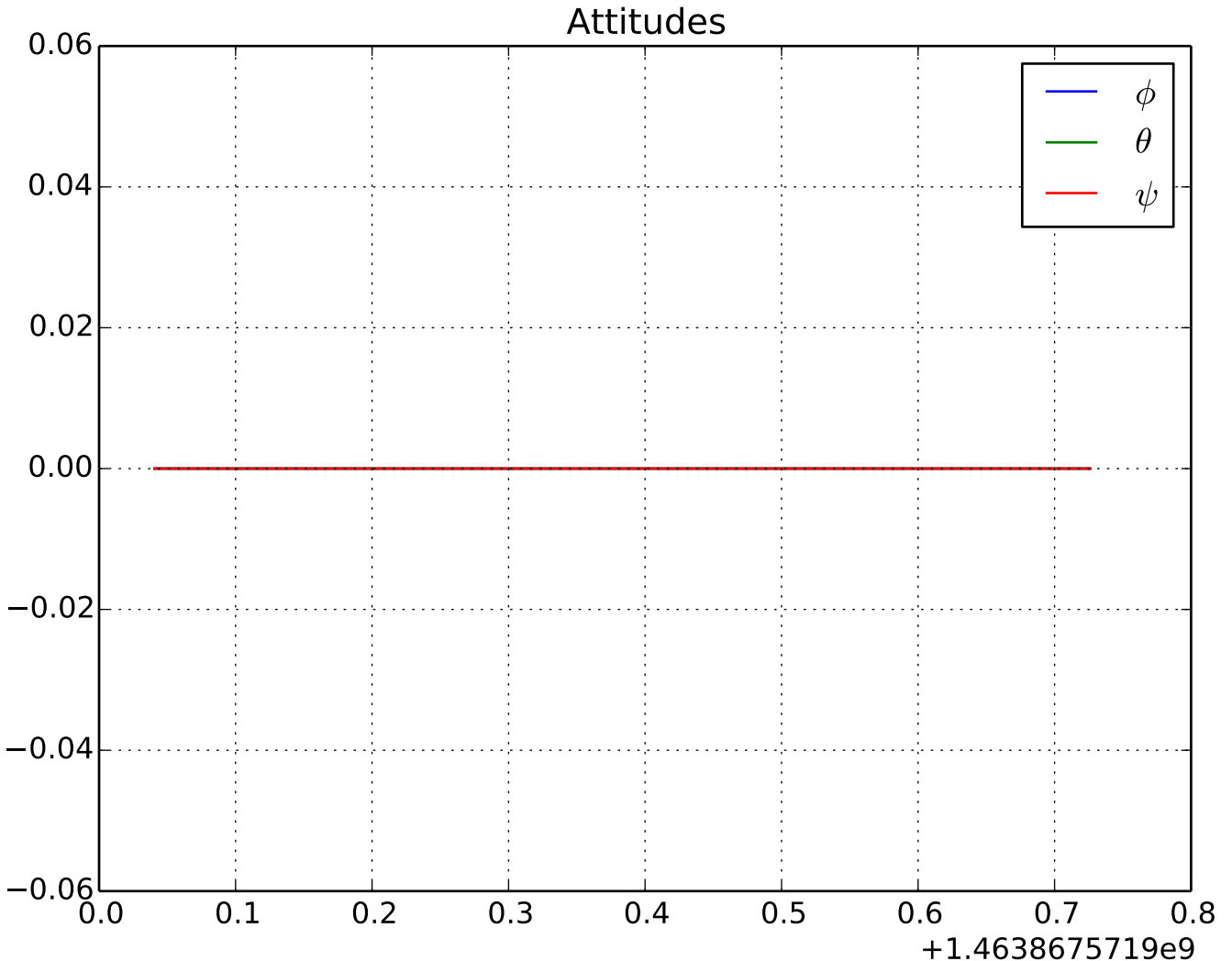
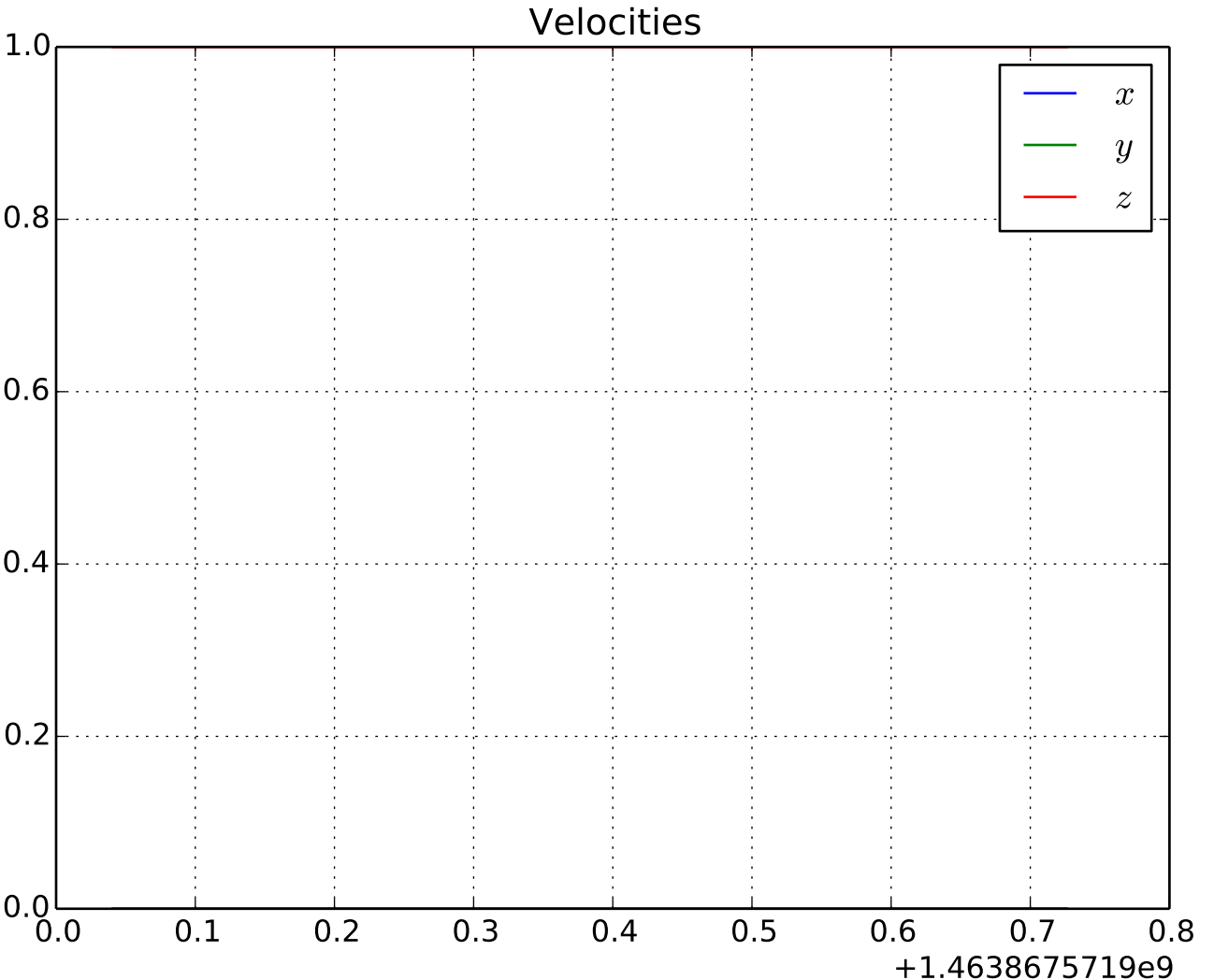

Positions
0.06
0.04
0.02
0.00
−0.02
−0.04
−0.06
0.0
0.1
0.2
0.3
0.4
0.5
0.6
0.7
0.8
+1.4638675719e9
x
y
z


Attitudes
0.06
0.04
0.02
0.00
−0.02
−0.04
−0.06
0.0
0.1
0.2
0.3
0.4
0.5
0.6
0.7
0.8
+1.4638675719e9
ϕ
θ
ψ


Velocities
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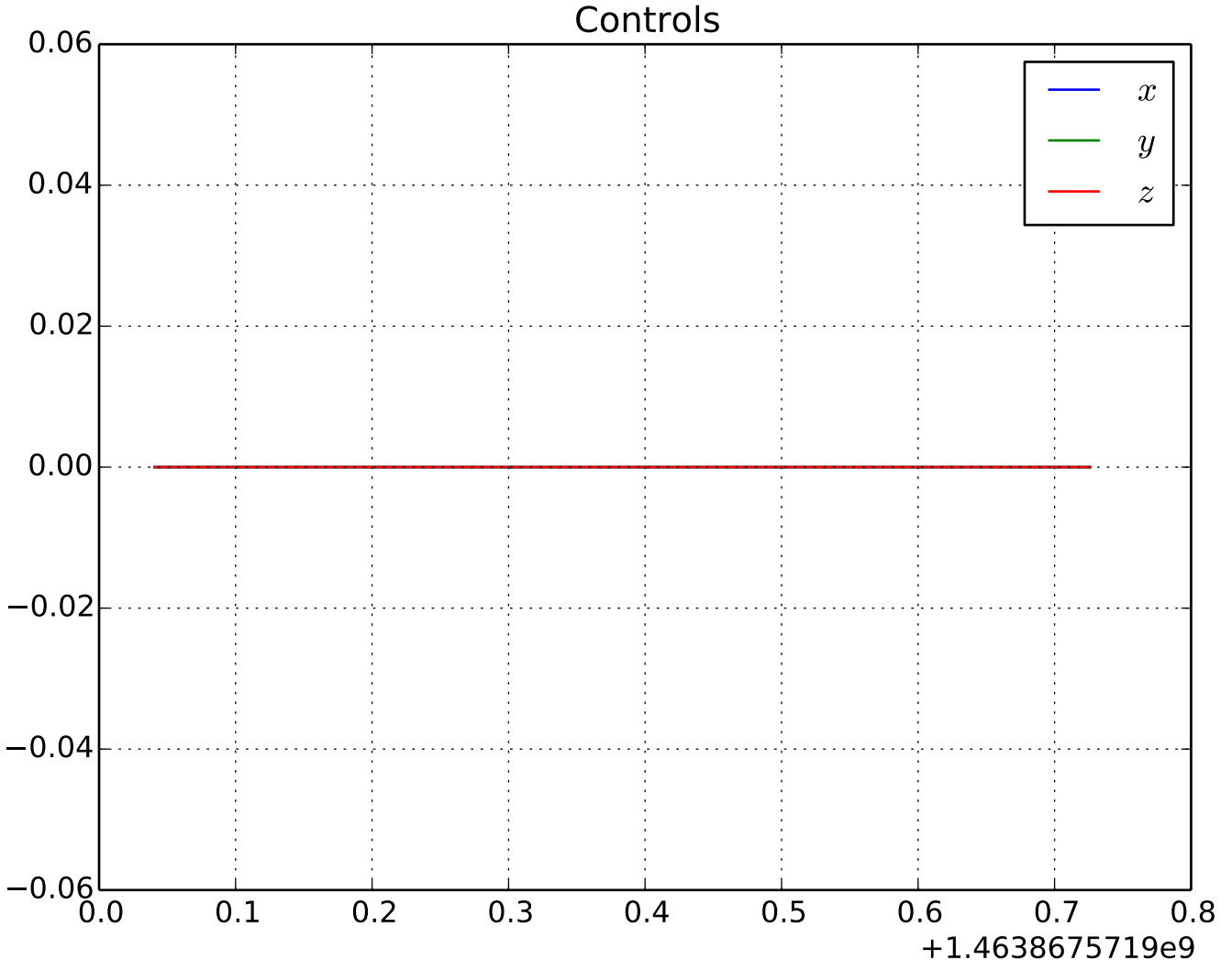
0.8
0.6
0.4
0.2
0.0
0.0
0.1
0.2
0.3
0.4
0.5
0.6
0.7
0.8
+1.4638675719e9
x
y
z


Controls
0.06
0.04
0.02
0.00
−0.02
−0.04
−0.06
0.0
0.1
0.2
0.3
0.4
0.5
0.6
0.7
0.8
+1.4638675719e9
x
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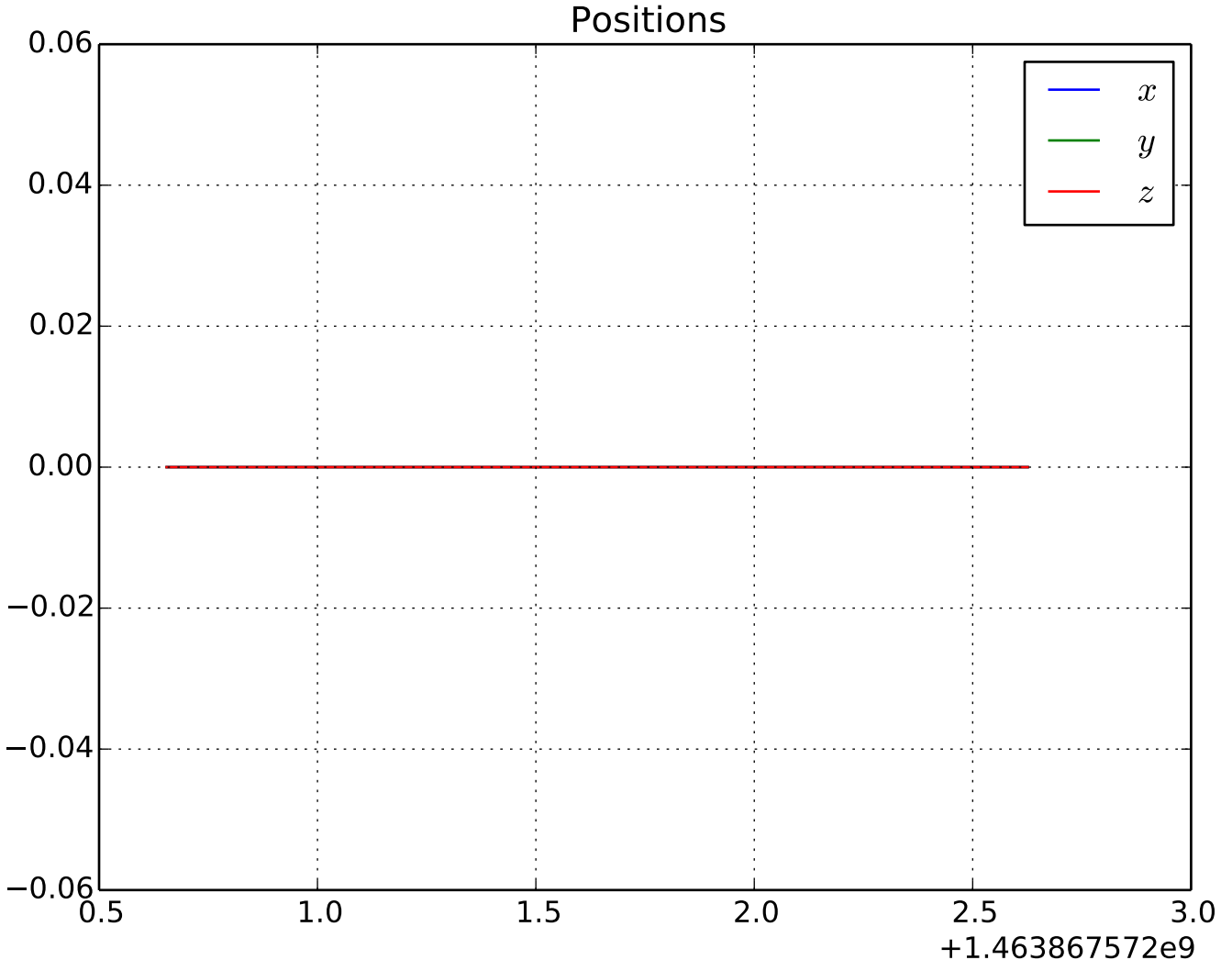
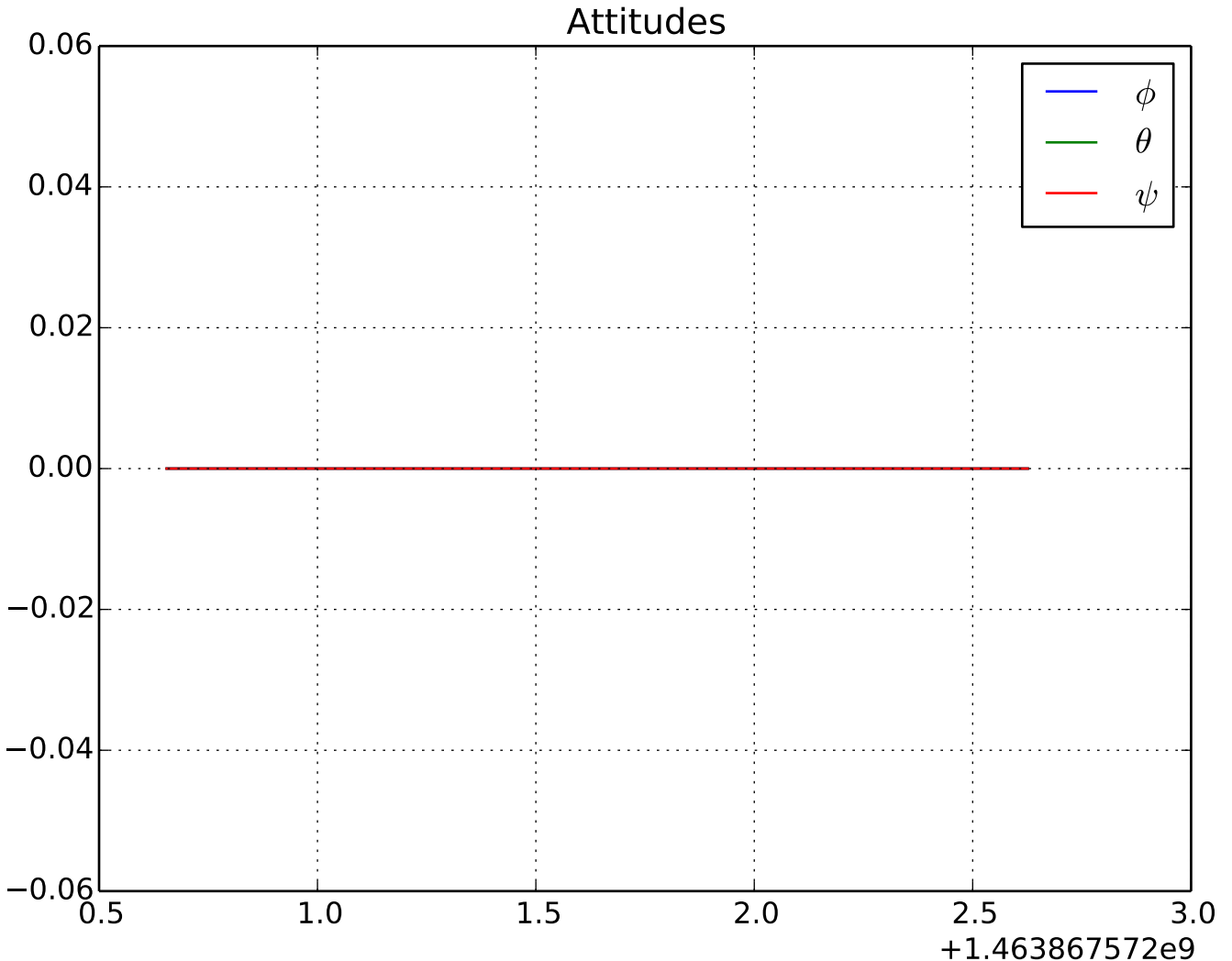
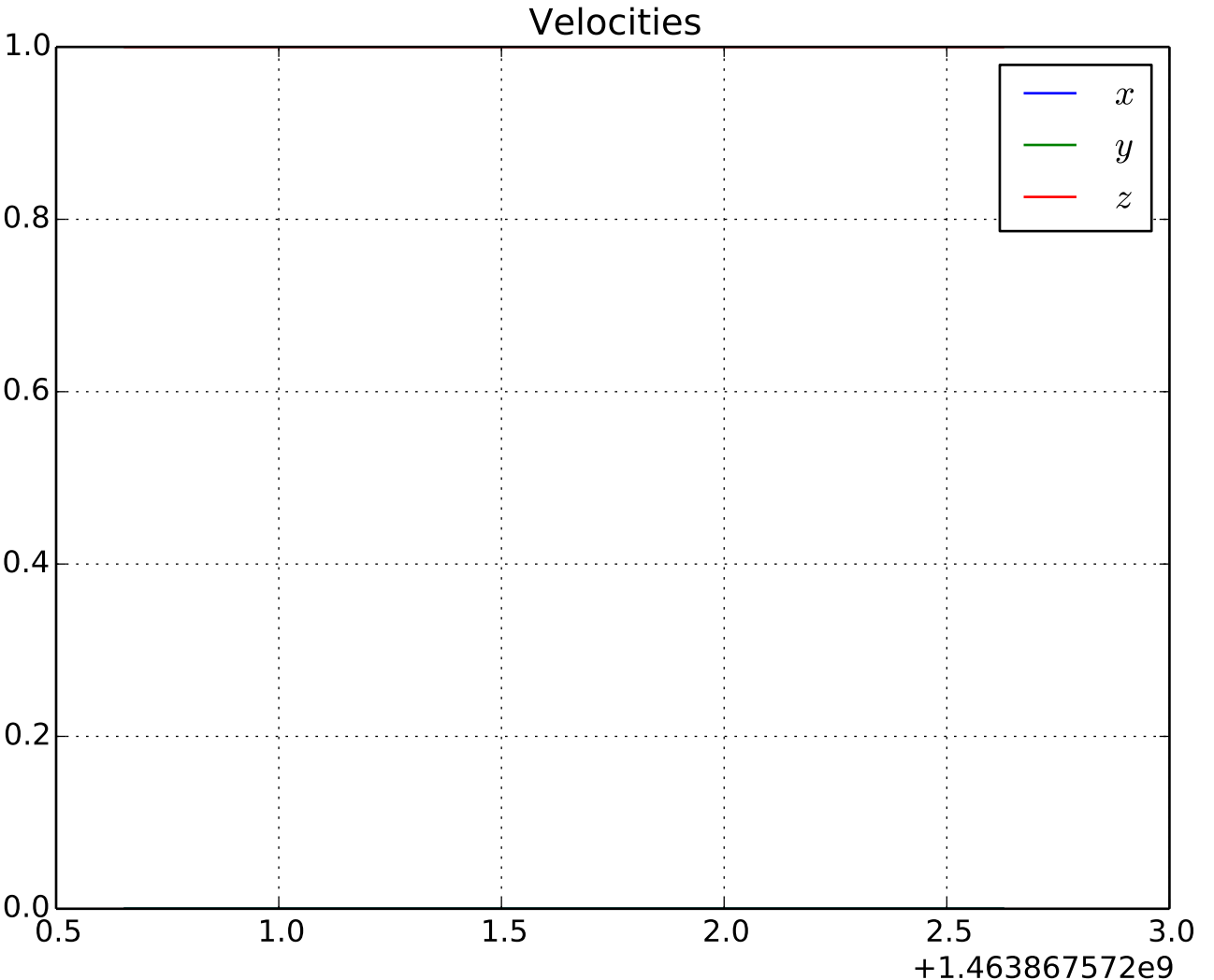
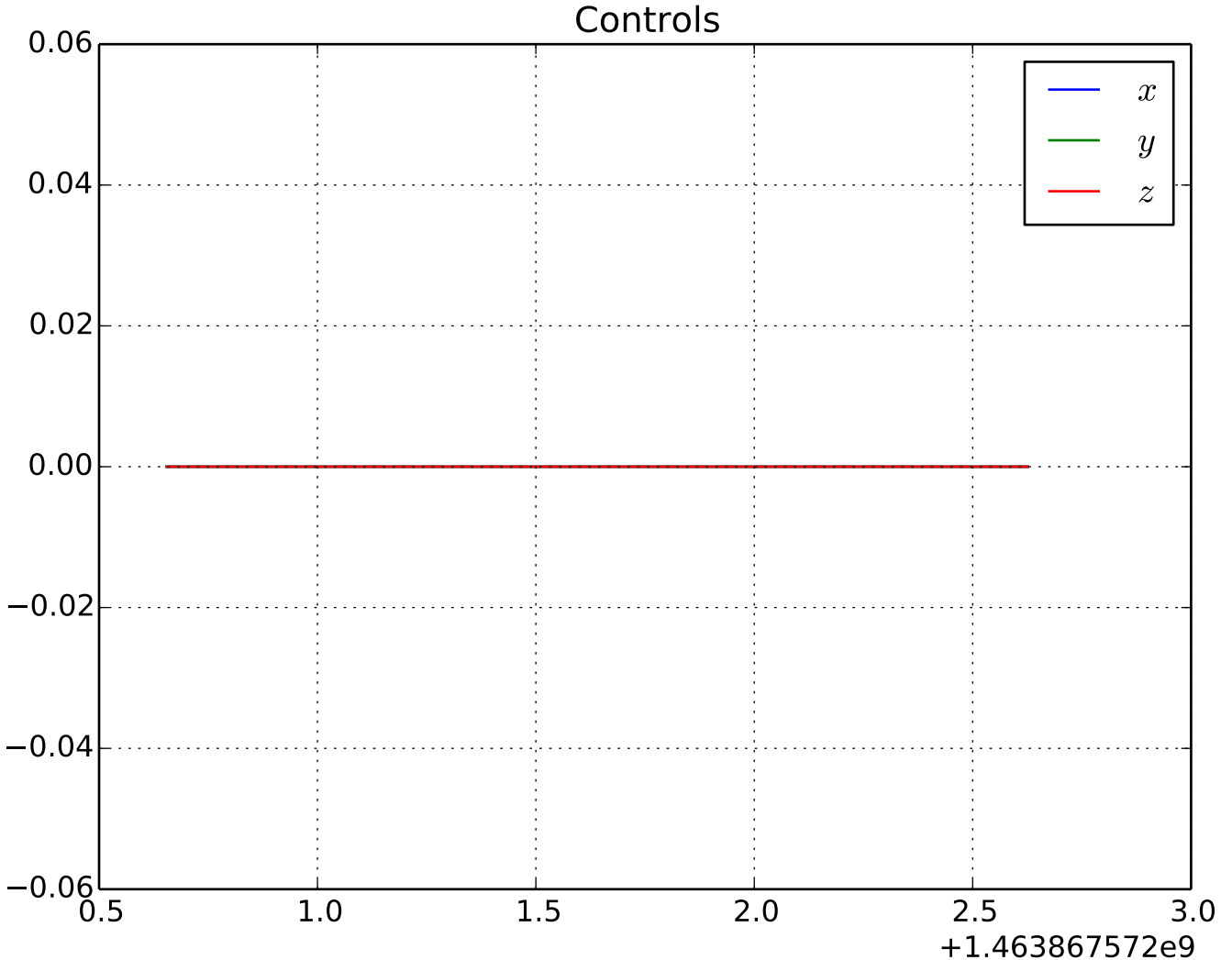

Positions
0.06
0.04
0.02
0.00
−0.02
−0.04
−0.06
0.5
1.0
1.5
2.0
2.5
3.0
+1.463867572e9
x
y
z


Attitudes
0.06
0.04
0.02
0.00
−0.02
−0.04
−0.06
0.5
1.0
1.5
2.0
2.5
3.0
+1.463867572e9
ϕ
θ
ψ


Velocities
1.0
0.8
0.6
0.4
0.2
0.0
0.5
1.0
1.5
2.0
2.5
3.0
+1.463867572e9
x
y
z


Controls
0.06
0.04
0.02
0.00
−0.02
−0.04
−0.06
0.5
1.0
1.5
2.0
2.5
3.0
+1.463867572e9
x
y
z

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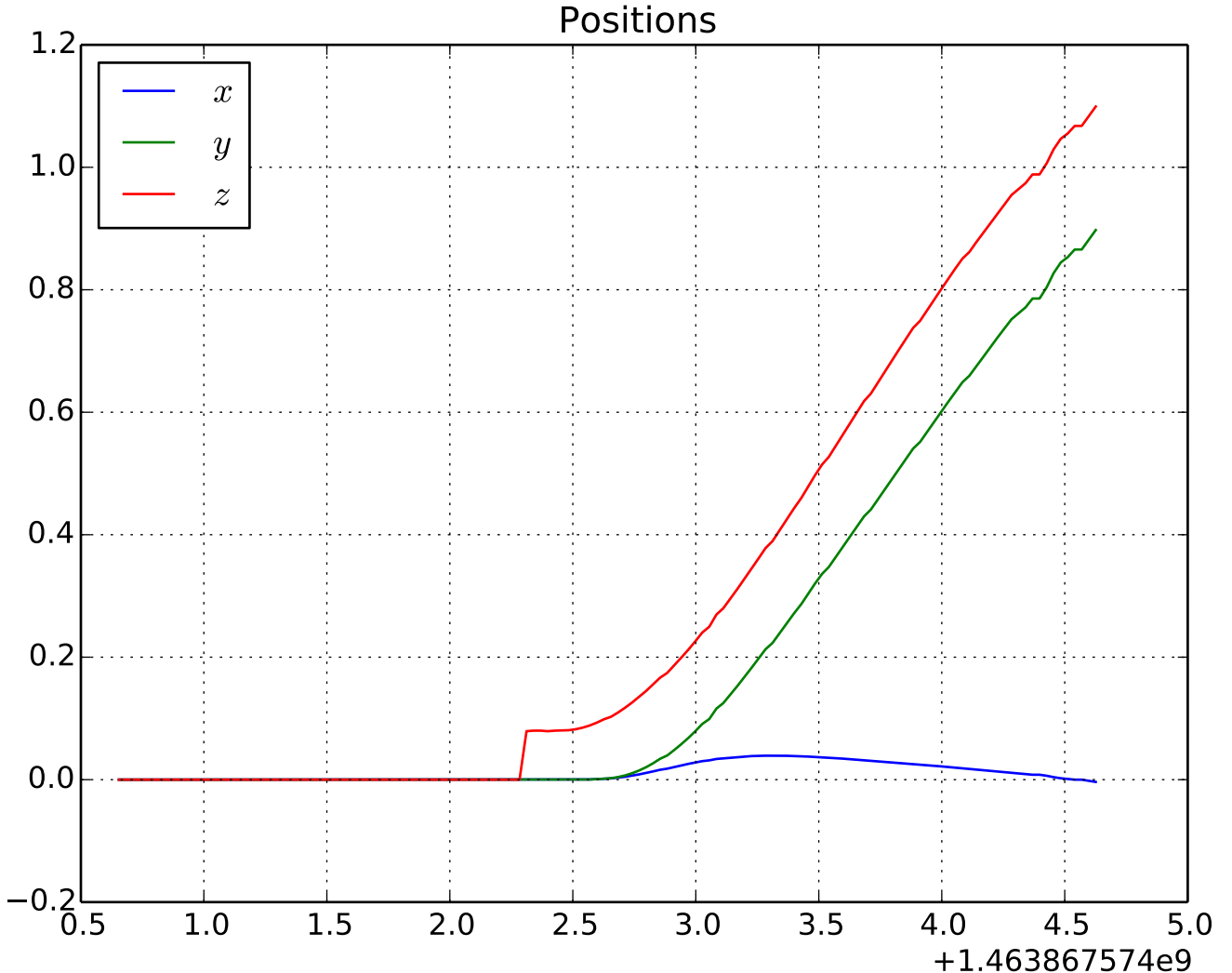
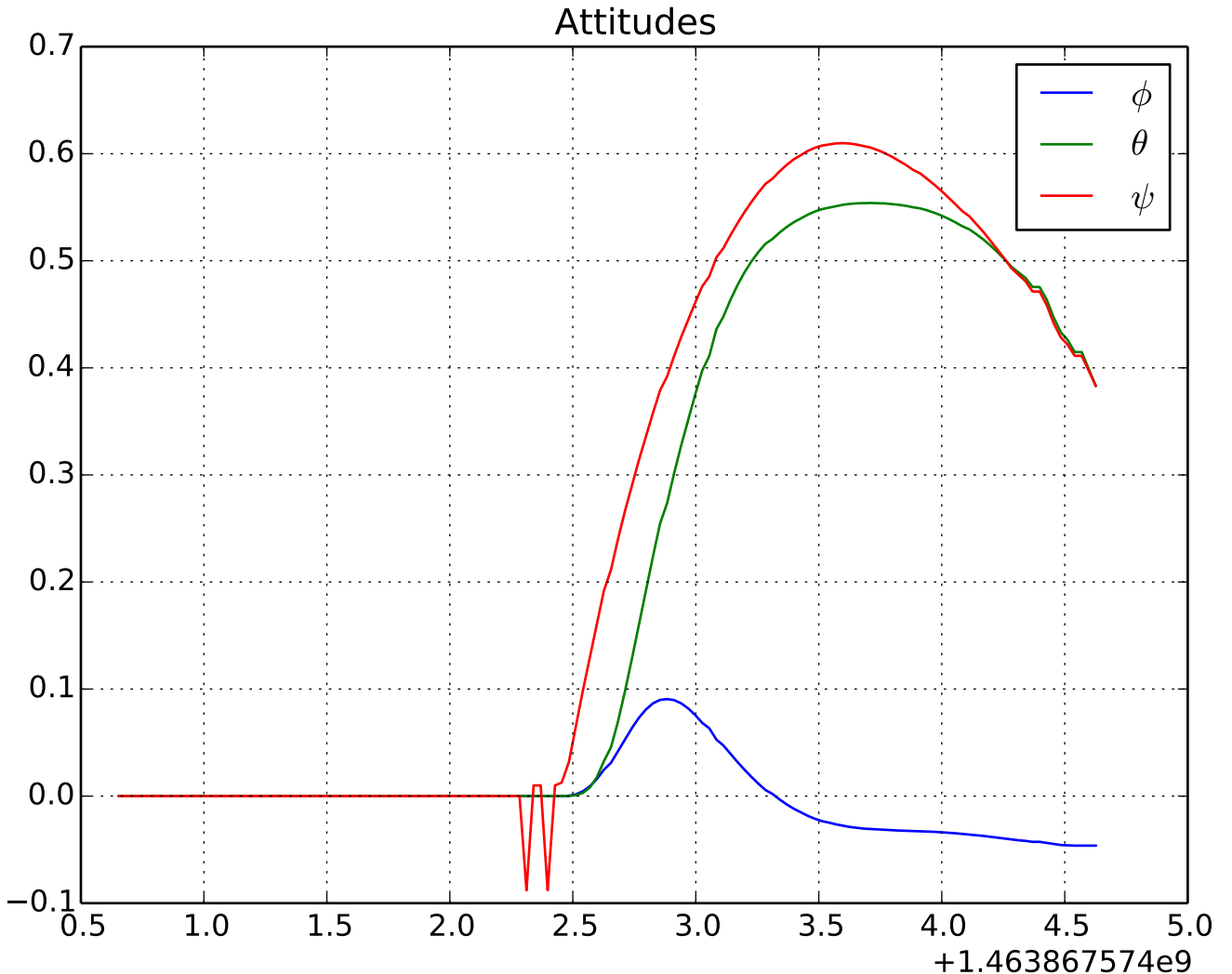
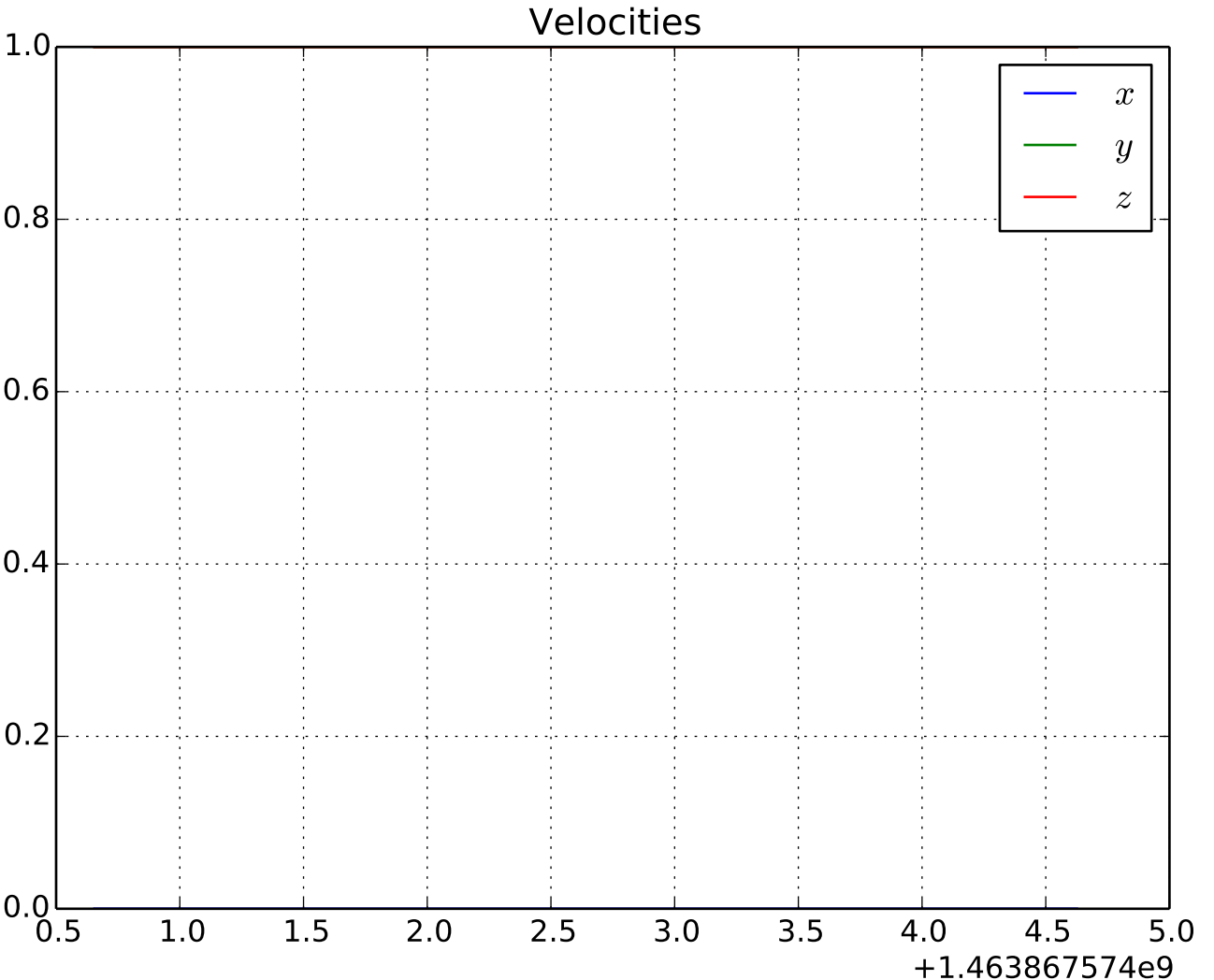
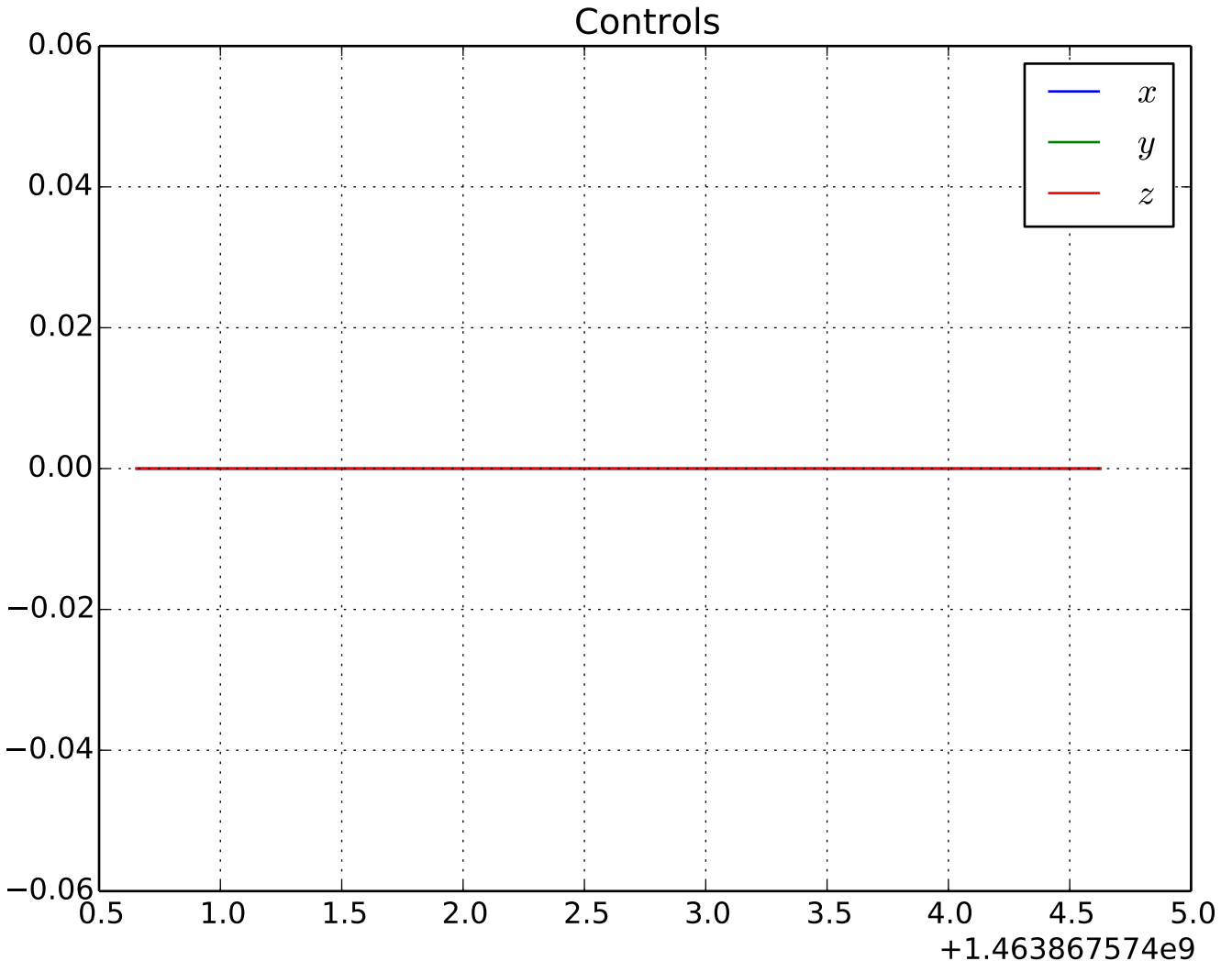

Positions
x
y
z
1.2
1.0
0.8
0.6
0.4
0.2
0.0
−0.2
0.5
1.0
1.5
2.0
2.5
3.0
3.5
4.0
4.5
5.0
+1.463867574e9


Attitudes
0.7
0.6
0.5
0.4
0.3
0.2
0.1
0.0
−0.1
0.5
1.0
1.5
2.0
2.5
3.0
3.5
4.0
4.5
5.0
+1.463867574e9
ϕ
θ
ψ


Velocities
1.0
0.8
0.6
0.4
0.2
0.0
0.5
1.0
1.5
2.0
2.5
3.0
3.5
4.0
4.5
5.0
+1.463867574e9
x
y
z


Controls
0.06
0.04
0.02
0.00
−0.02
−0.04
−0.06
0.5
1.0
1.5
2.0
2.5
3.0
3.5
4.0
4.5
5.0
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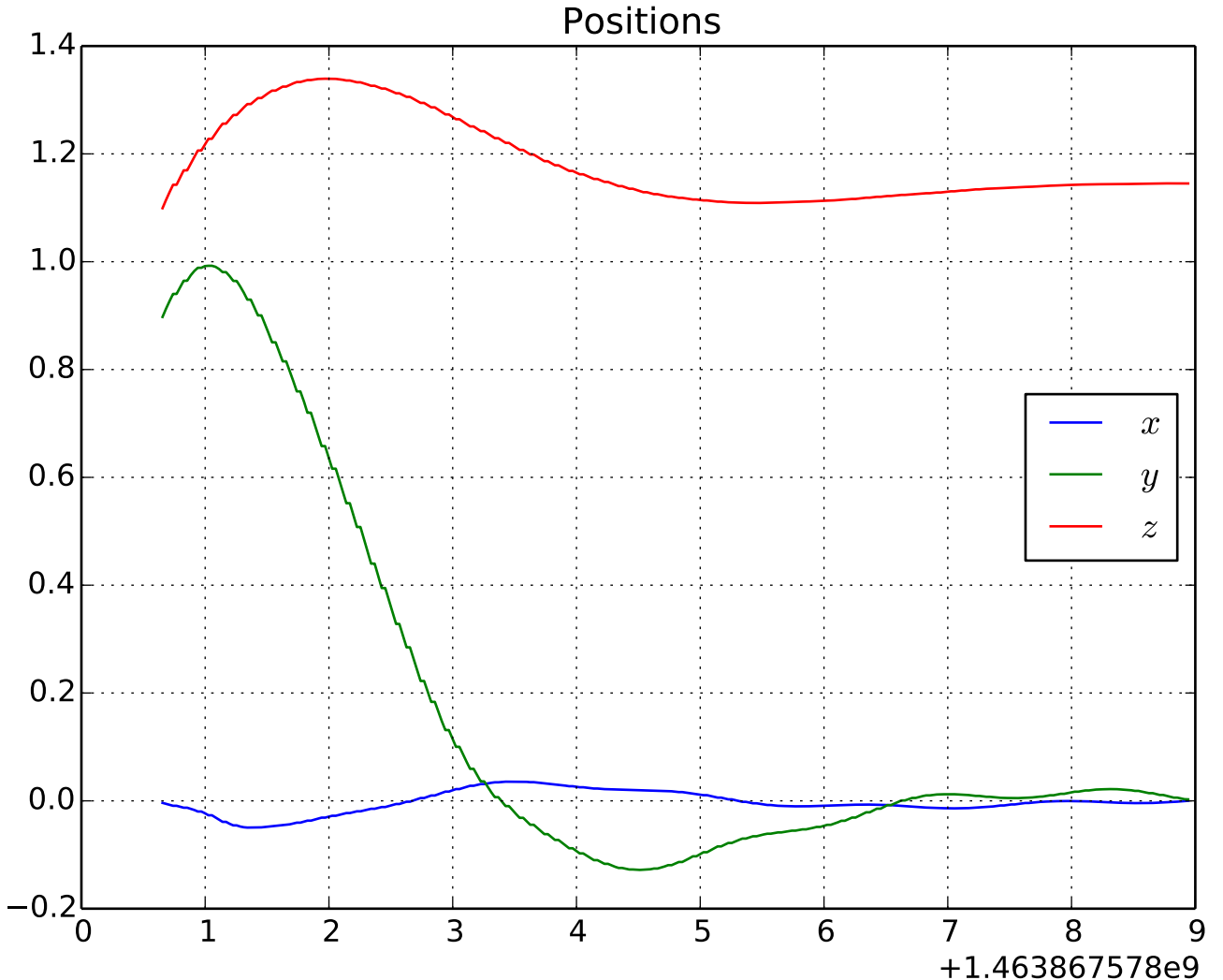
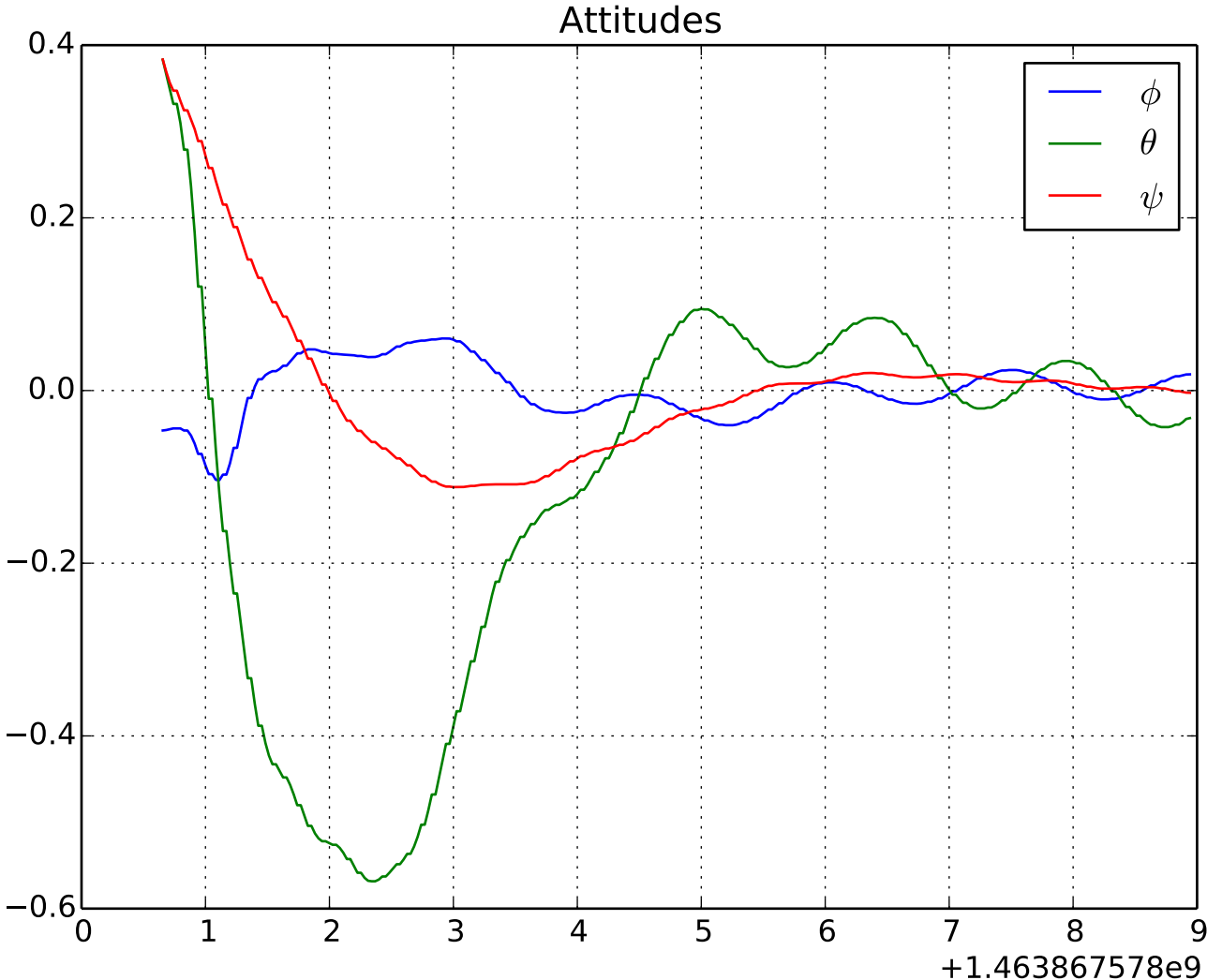

Positions
1.4
1.2
1.0
0.8
0.6
0.4
0.2
0.0
−0.2
0
1
2
3
4
5
6
7
8
9
+1.463867578e9
x
y
z


Attitudes
0.4
0.2
0.0
−0.2
−0.4
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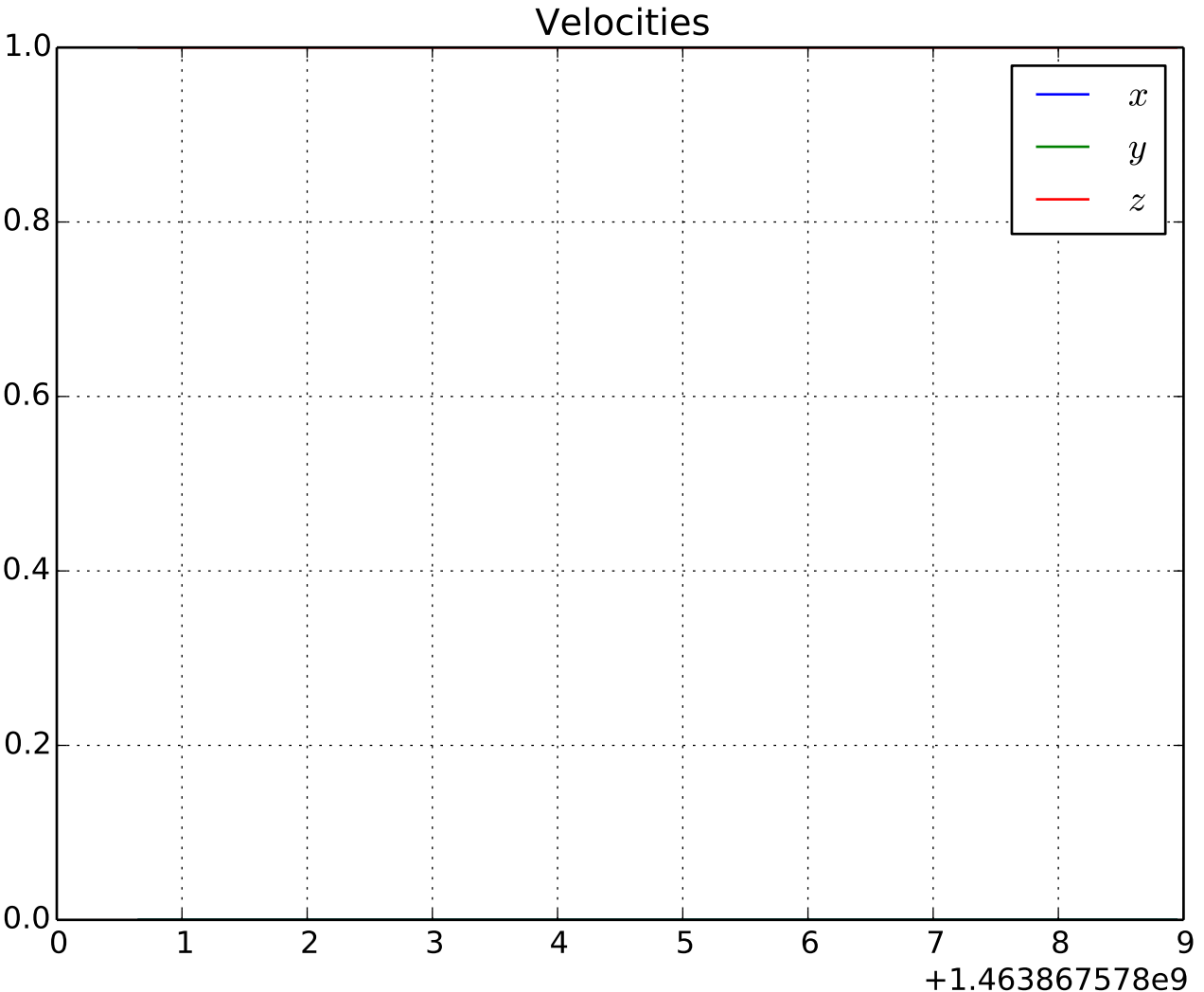
0
1
2
3
4
5
6
7
8
9
+1.463867578e9
ϕ
θ
ψ


Velocities
1.0
0.8
0.6
0.4
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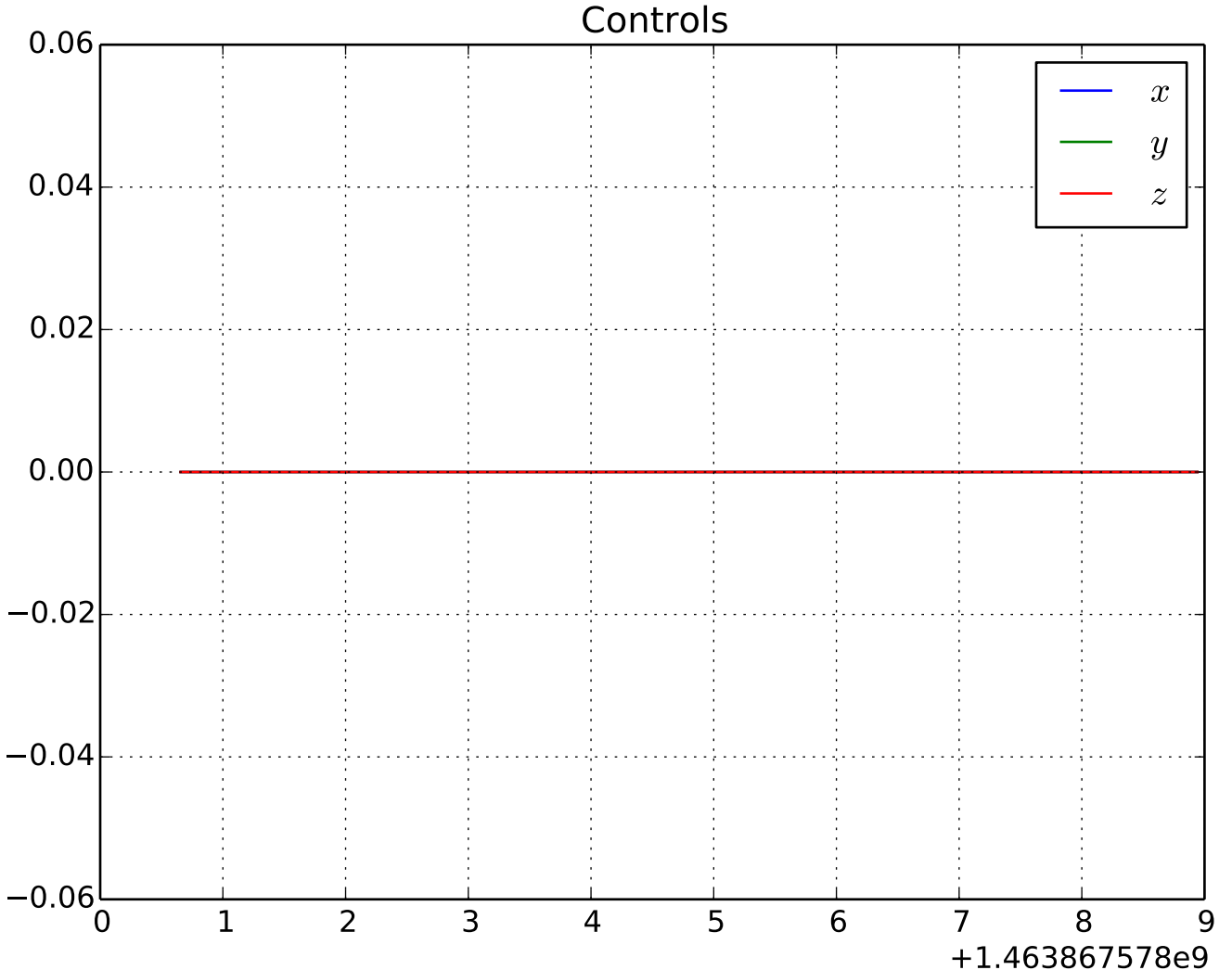
0
1
2
3
4
5
6
7
8
9
+1.463867578e9
x
y
z


Controls
0.06
0.04
0.02
0.00
−0.02
−0.04
−0.06
0
1
2
3
4
5
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x
y
z