RL6-1

MASS = 1.1813898e+01 GRAM

CENTER OF GRAVITY with respect to RL6 coordinate frame:

X Y Z 2.2433938e+01 0.0000000e+00 -2.0759830e+01 MM

INERTIA with respect to RL6 coordinate frame: (GRAM \* MM^2)

INERTIA TENSOR:

Ixx Ixy Ixz 6.5993698e+03 0.0000000e+00 5.4967624e+03

Iyx Iyy Iyz 0.0000000e+00 1.5337900e+04 0.0000000e+00

Izx Izy Izz 5.4967624e+03 0.0000000e+00 1.0065040e+04

INERTIA at CENTER OF GRAVITY with respect to RL6 coordinate frame: (GRAM \* MM^2)

INERTIA TENSOR:

Ixx Ixy Ixz 1.5079276e+03 0.0000000e+00 -5.2622000e+00

Iyx Iyy Iyz 0.0000000e+00 4.3007402e+03 0.0000000e+00

Izx Izy Izz -5.2622000e+00 0.0000000e+00 4.1193223e+03

RL6-2

MASS = 5.7530951e+01 GRAM

CENTER OF GRAVITY with respect to RL6-2 coordinate frame:

X Y Z 0.0000000e+00 -1.2500000e+01 -5.0643542e-01 MM

INERTIA with respect to RL6-2 coordinate frame: (GRAM \* MM^2)

INERTIA TENSOR:

Ixx Ixy Ixz 4.5641947e+04 -1.0269354e-02 0.0000000e+00

Iyx Iyy Iyz -1.0269354e-02 7.3765773e+04 -3.6419639e+02

Izx Izy Izz 0.0000000e+00 -3.6419639e+02 1.1910638e+05

INERTIA at CENTER OF GRAVITY with respect to RL6-2 coordinate frame: (GRAM \* MM^2)

INERTIA TENSOR:

Ixx Ixy Ixz 3.6637981e+04 -6.3540504e-03 0.0000000e+00

Iyx Iyy Iyz -6.3540504e-03 7.3751018e+04 0.0000000e+00

Izx Izy Izz 0.0000000e+00 0.0000000e+00 1.1011717e+05

LL6-1

MASS = 1.1813898e+01 GRAM

CENTER OF GRAVITY with respect to LL6 coordinate frame:

X Y Z 2.2433938e+01 0.0000000e+00 -2.0759830e+01 MM

INERTIA with respect to LL6 coordinate frame: (GRAM \* MM^2)

INERTIA TENSOR:

Ixx Ixy Ixz 6.5993698e+03 0.0000000e+00 5.4967624e+03

Iyx Iyy Iyz 0.0000000e+00 1.5337900e+04 0.0000000e+00

Izx Izy Izz 5.4967624e+03 0.0000000e+00 1.0065040e+04

INERTIA at CENTER OF GRAVITY with respect to LL6 coordinate frame: (GRAM \* MM^2)

INERTIA TENSOR:

Ixx Ixy Ixz 1.5079276e+03 0.0000000e+00 -5.2622000e+00

Iyx Iyy Iyz 0.0000000e+00 4.3007402e+03 0.0000000e+00

Izx Izy Izz -5.2622000e+00 0.0000000e+00 4.1193223e+03

LL6-2

MASS = 5.7530951e+01 GRAM

CENTER OF GRAVITY with respect to RL6-2 coordinate frame:

X Y Z 0.0000000e+00 8.2500000e+01 -5.0643542e-01 MM

INERTIA with respect to RL6-2 coordinate frame: (GRAM \* MM^2)

INERTIA TENSOR:

Ixx Ixy Ixz 4.2822277e+05 1.9486951e-02 0.0000000e+00

Iyx Iyy Iyz 1.9486951e-02 7.3765773e+04 2.4036962e+03

Izx Izy Izz 0.0000000e+00 2.4036962e+03 5.0168720e+05

INERTIA at CENTER OF GRAVITY with respect to RL6-2 coordinate frame: (GRAM \* MM^2)

INERTIA TENSOR:

Ixx Ixy Ixz 3.6637981e+04 -6.3540503e-03 0.0000000e+00

Iyx Iyy Iyz -6.3540503e-03 7.3751018e+04 0.0000000e+00

Izx Izy Izz 0.0000000e+00 0.0000000e+00 1.1011717e+05

RL1-RL2

24 0 -28.5

LL1-LL2

24 0 -28.5