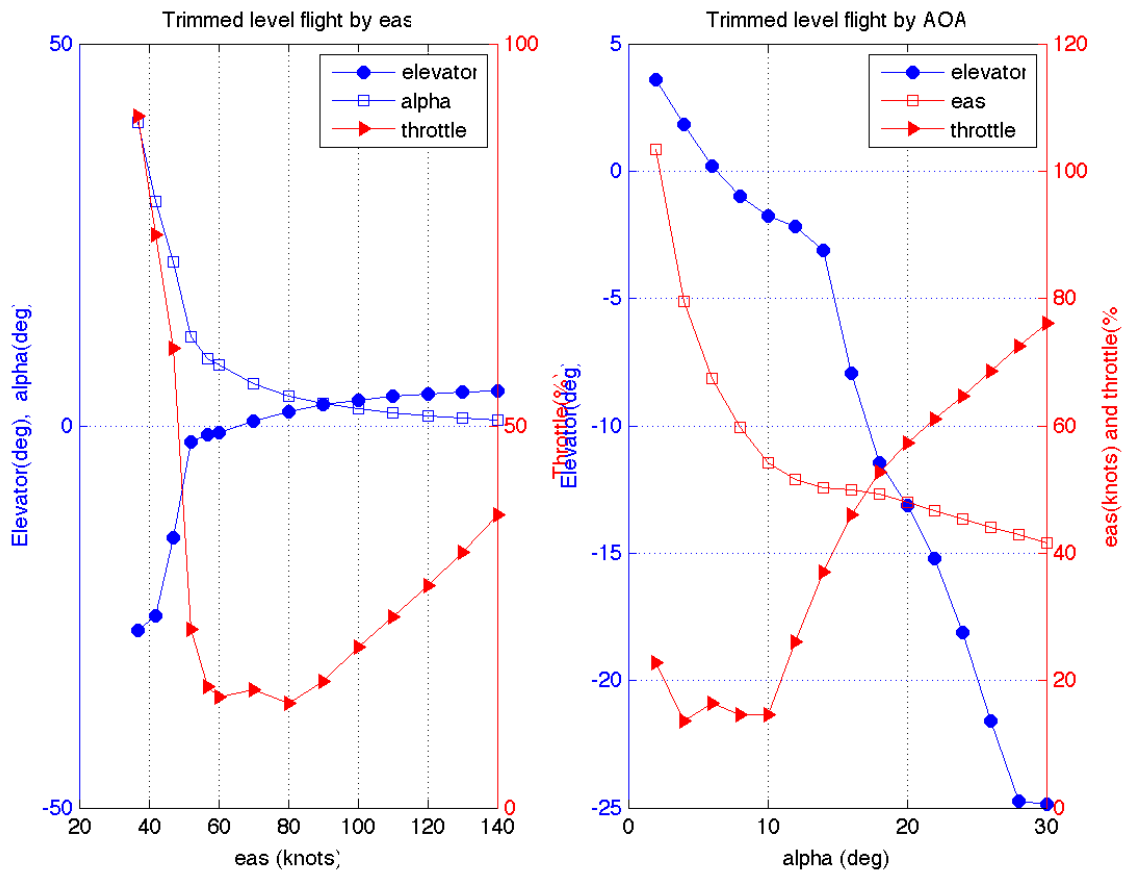
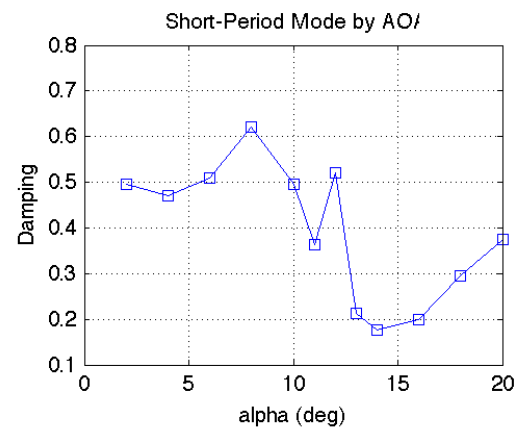
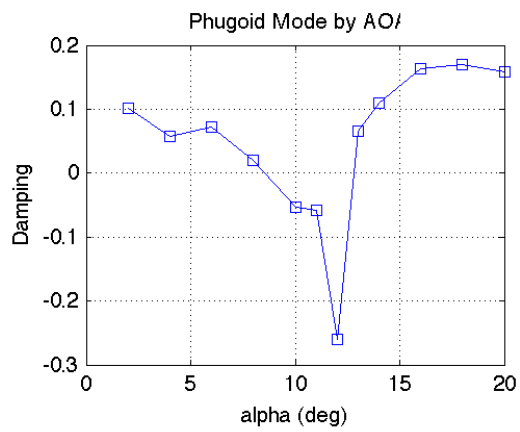
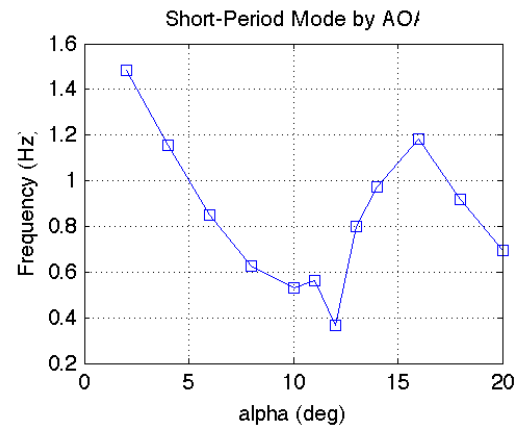
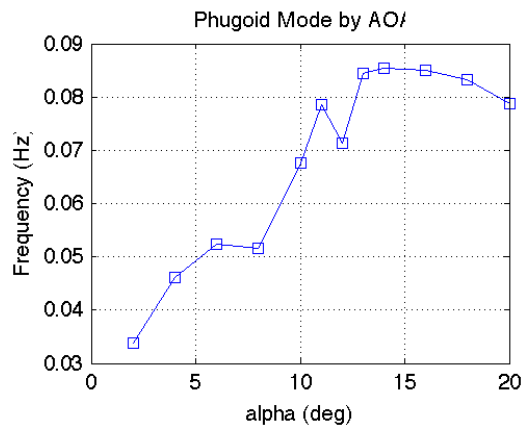


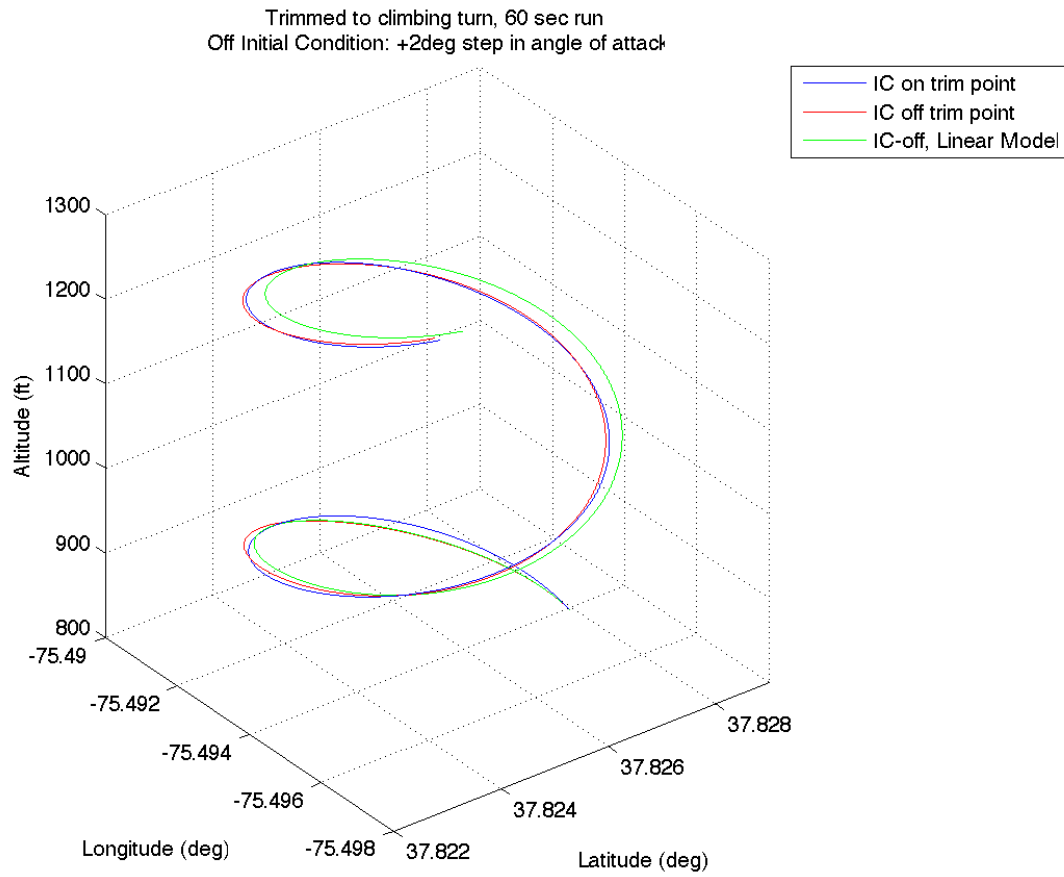
Example-1: Linear and nonlinear response to pitch-yaw-roll doublet sequence



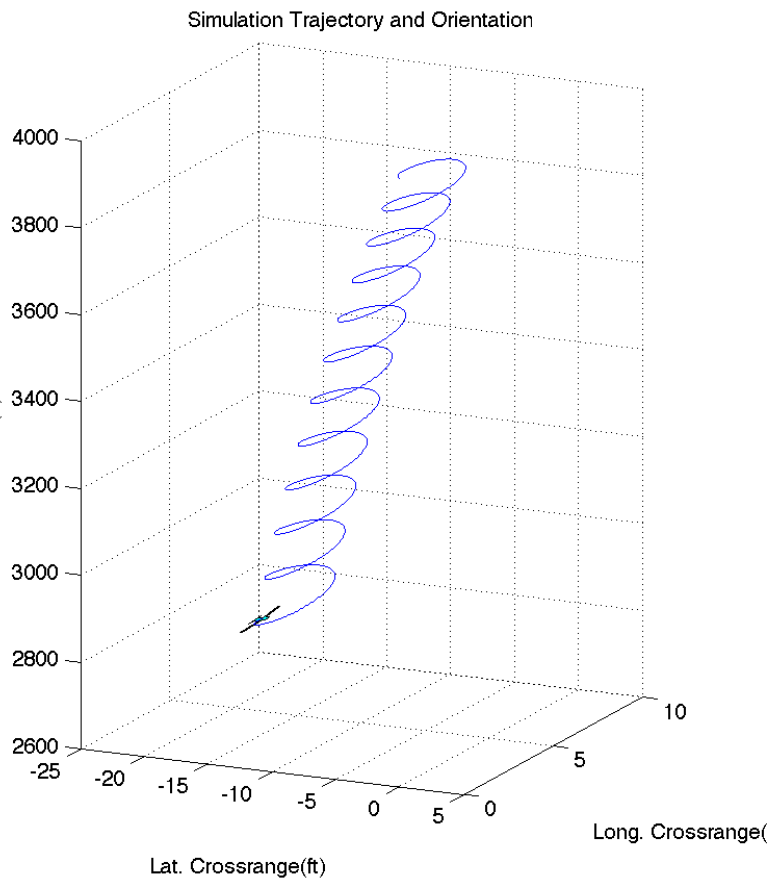
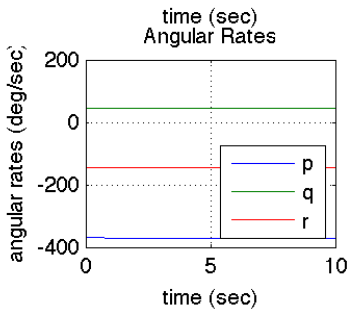
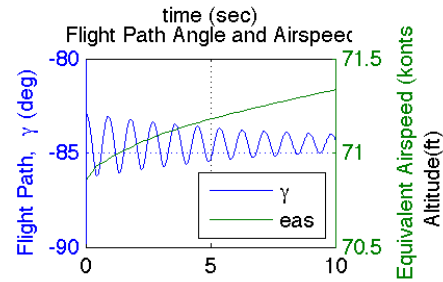
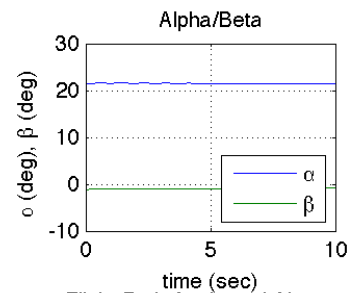
Example-2: Locus of trim states and surface commands for level flight



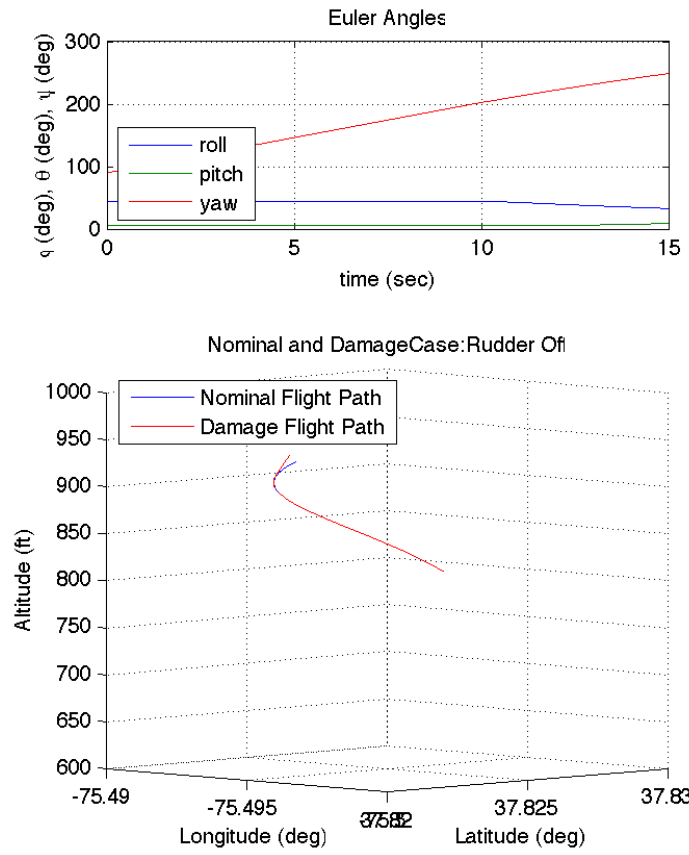
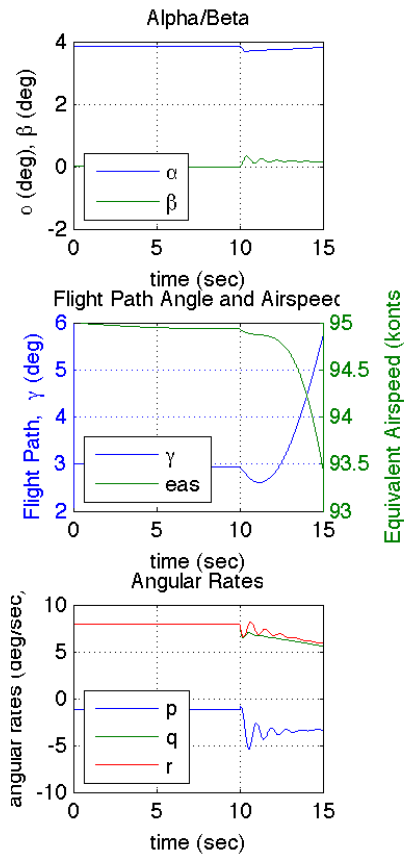
Example-3: Frequency and damping of decoupled linear models in level flight



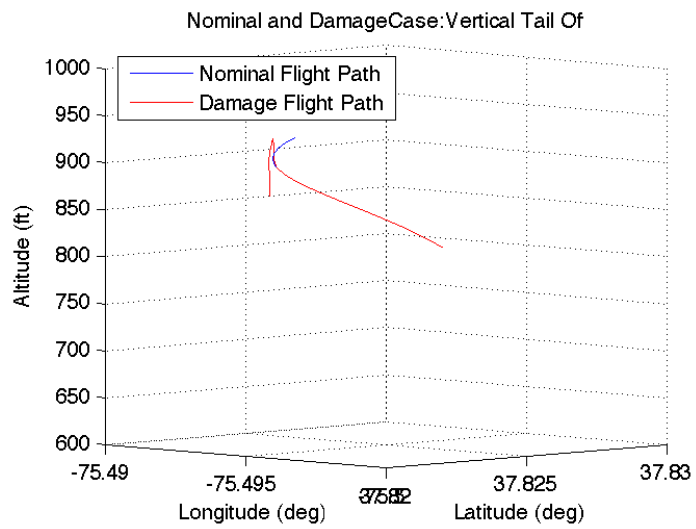
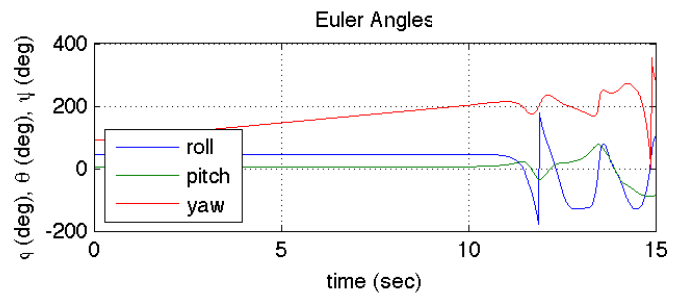
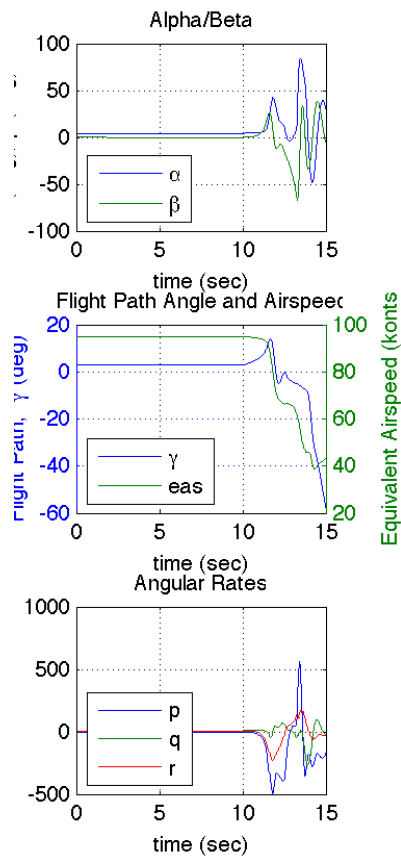
Example-4: Trim to climbing turn, linear and nonlinear response to perturbed initial condition



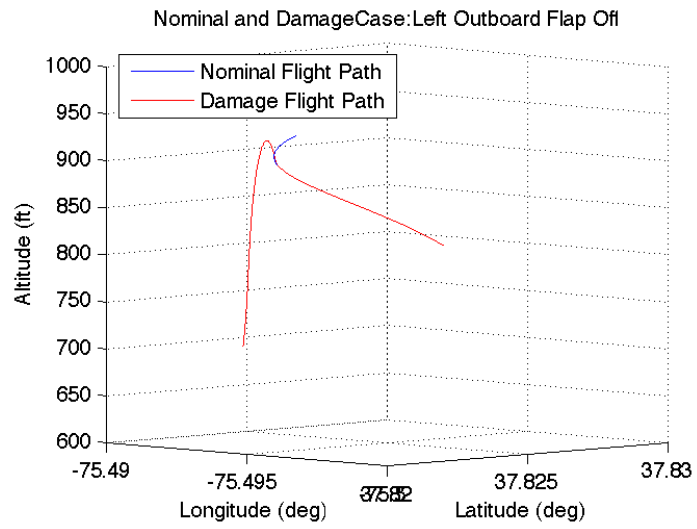
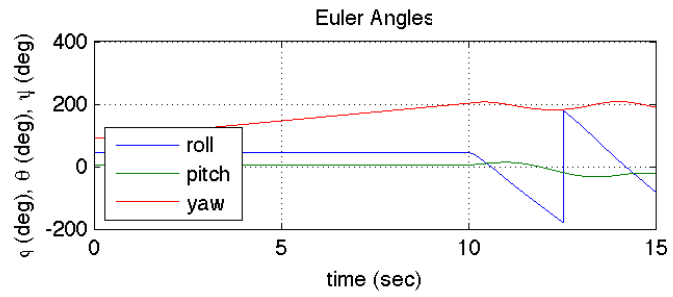
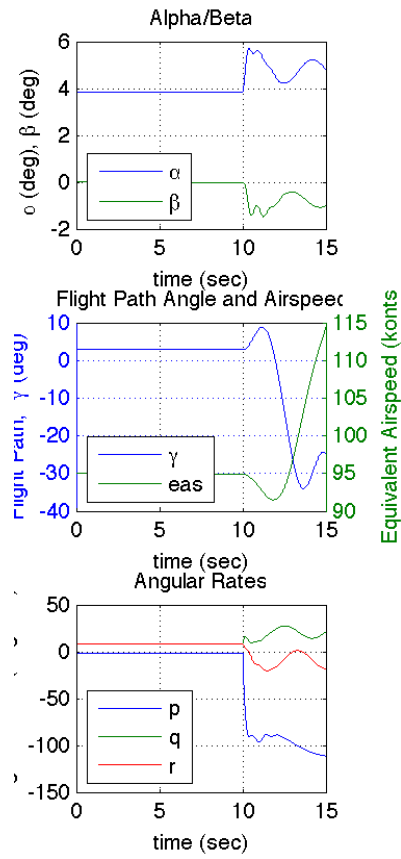
Example-5: Trim to spin equilibrium condition



Example-6: DamageCase-01, Rudder Off

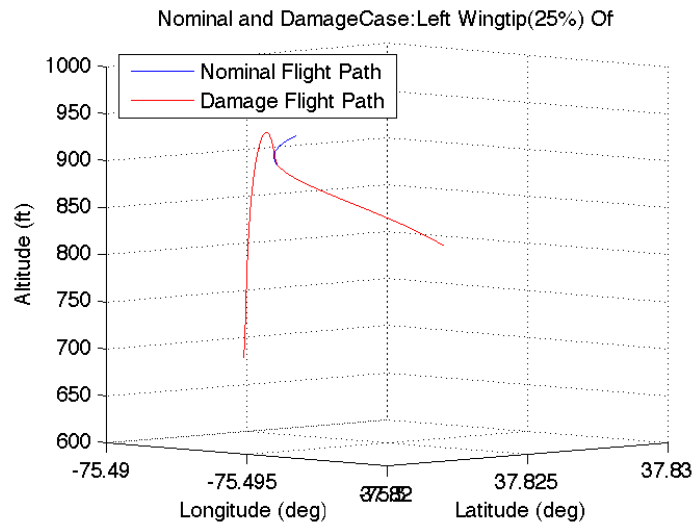
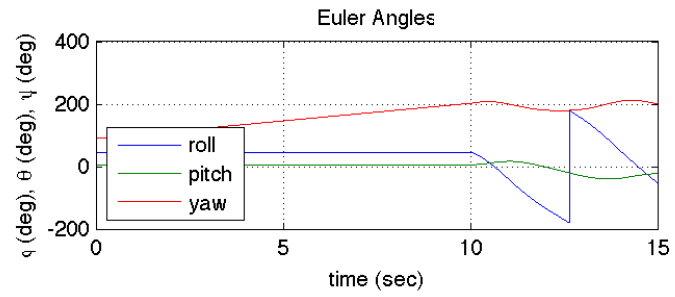
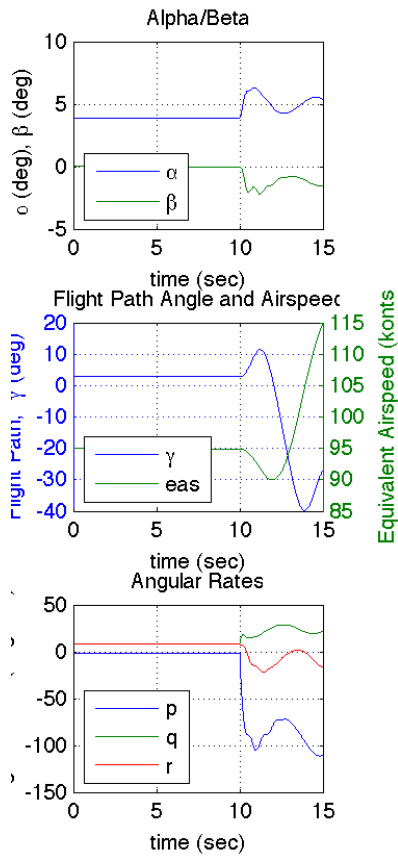


Example-6: DamageCase-02, Vertical Tail Off

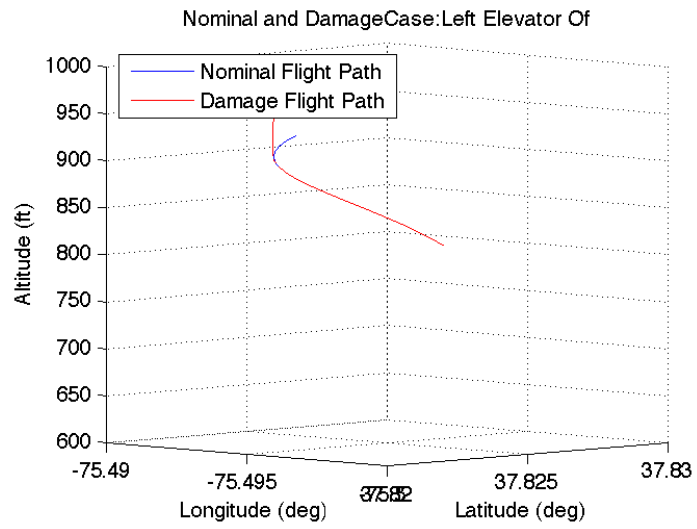
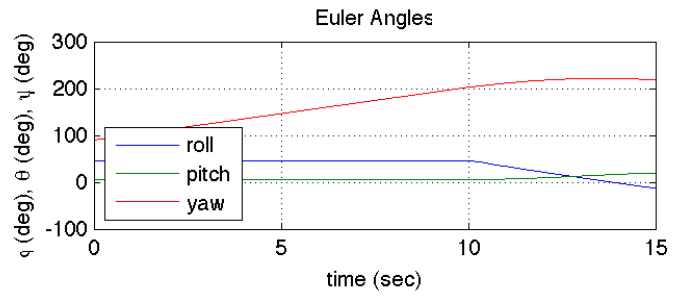
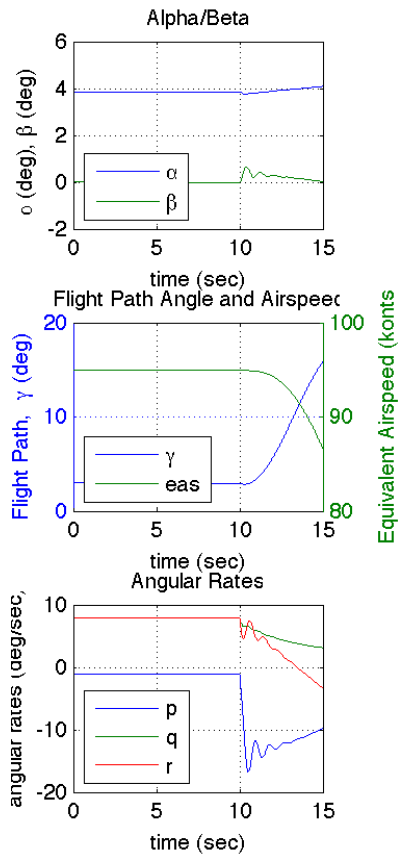


Example-6: DamageCase-03, Left Outboard Flap Off

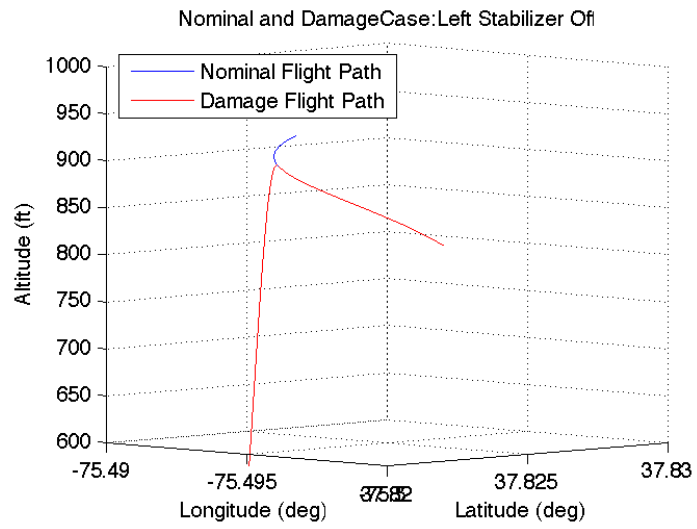
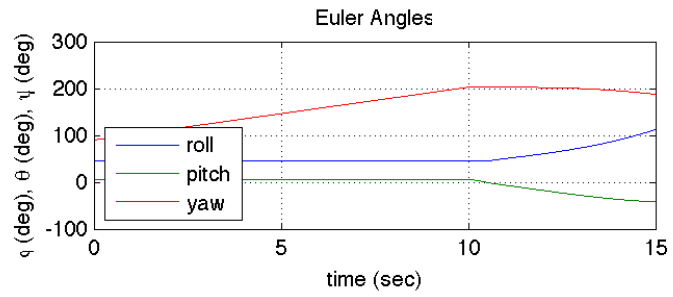
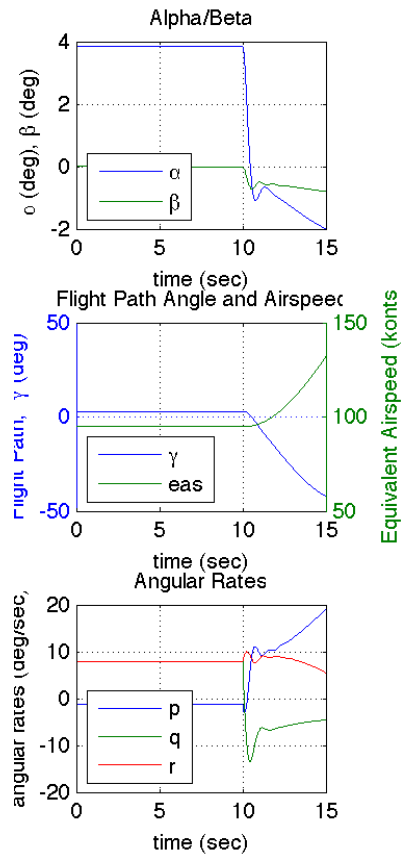




Example-6: DamageCase-04, Left Wingtip(25%) Off



Example-6: DamageCase-05, Left Elevator Off



Example-6: DamageCase-06, Left Stabilizer Off