

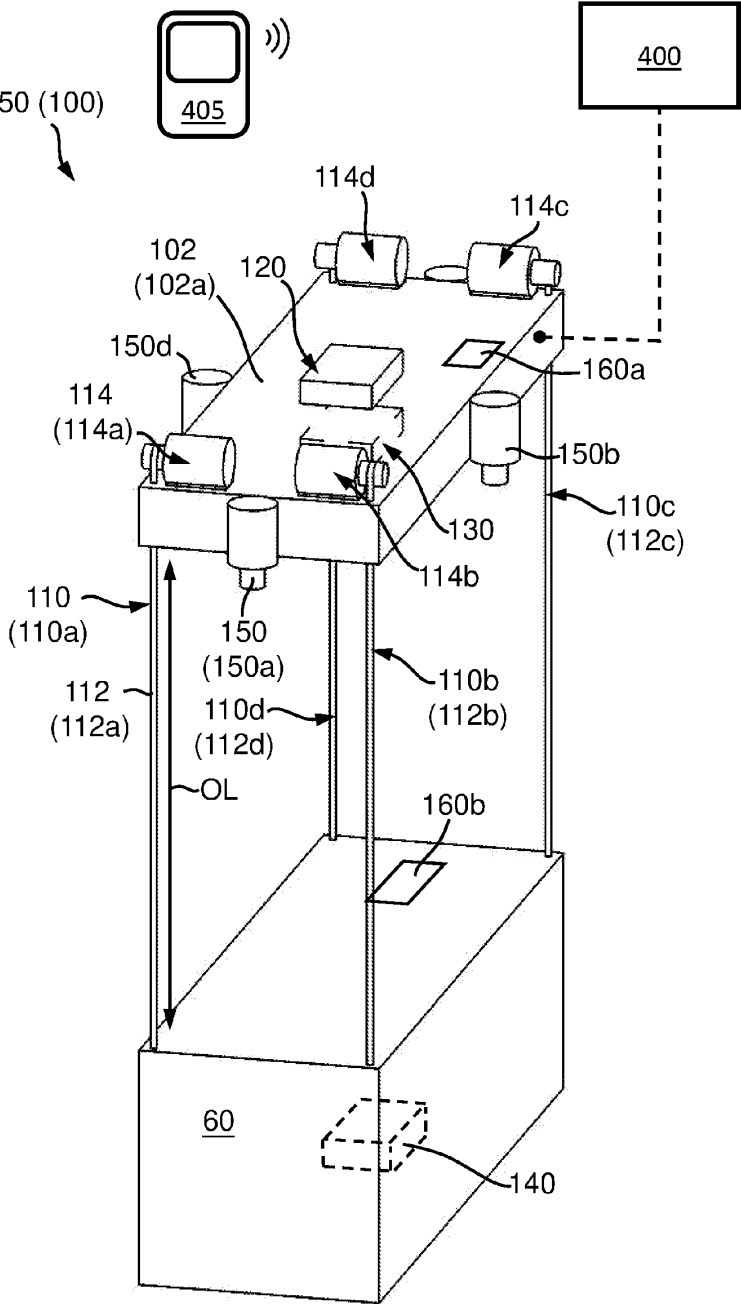


FIG. 1

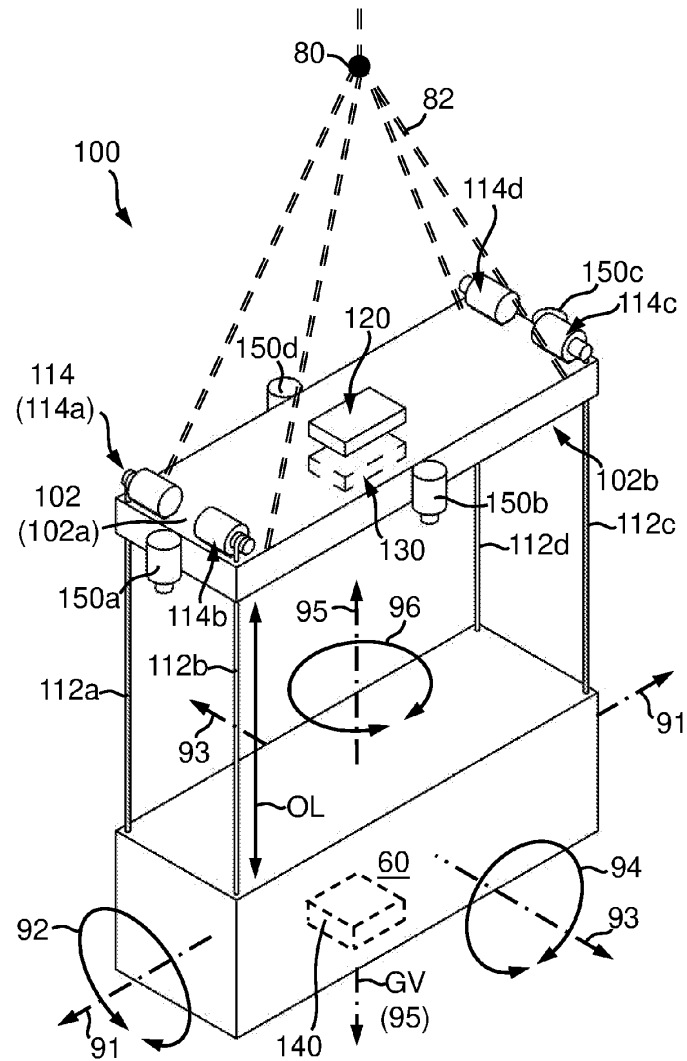


FIG. 2

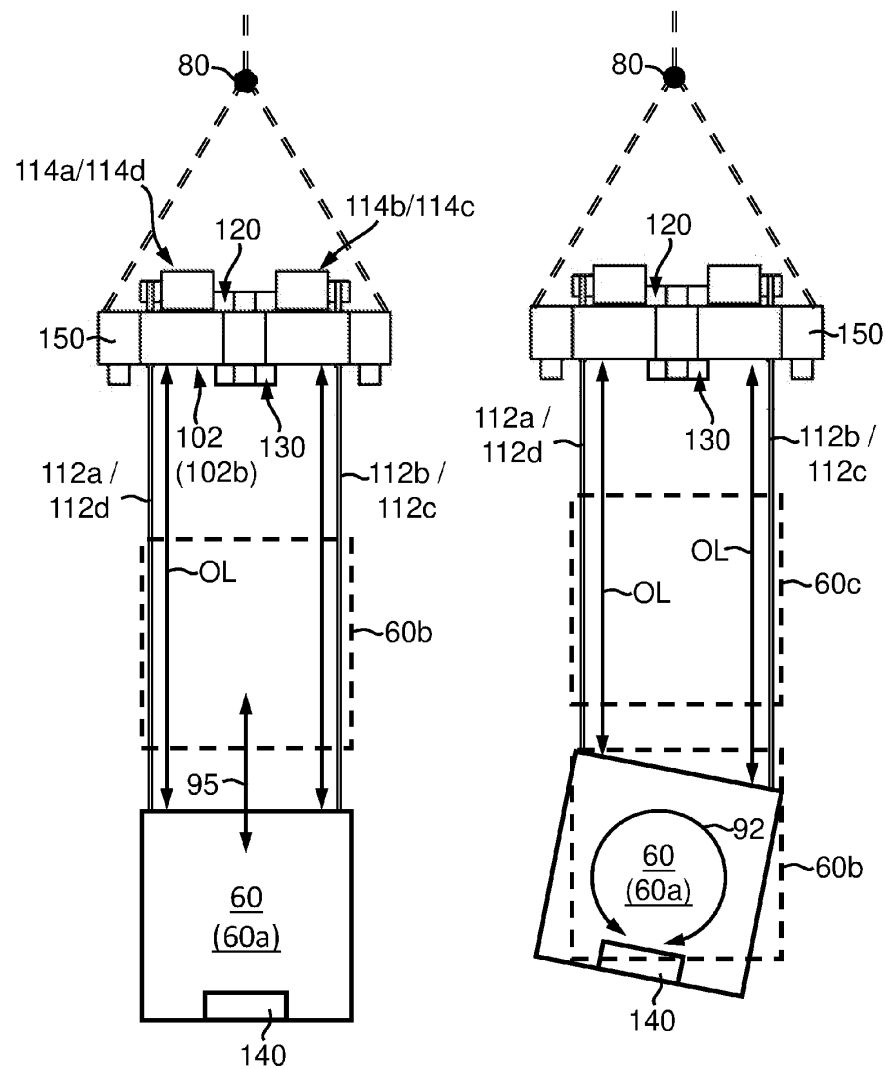


FIG. 3A

FIG. 3B

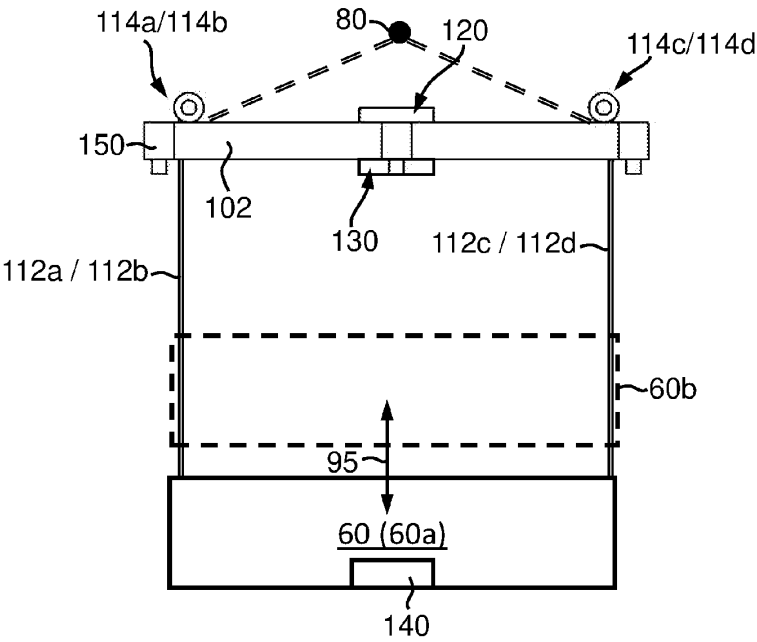


FIG. 4A

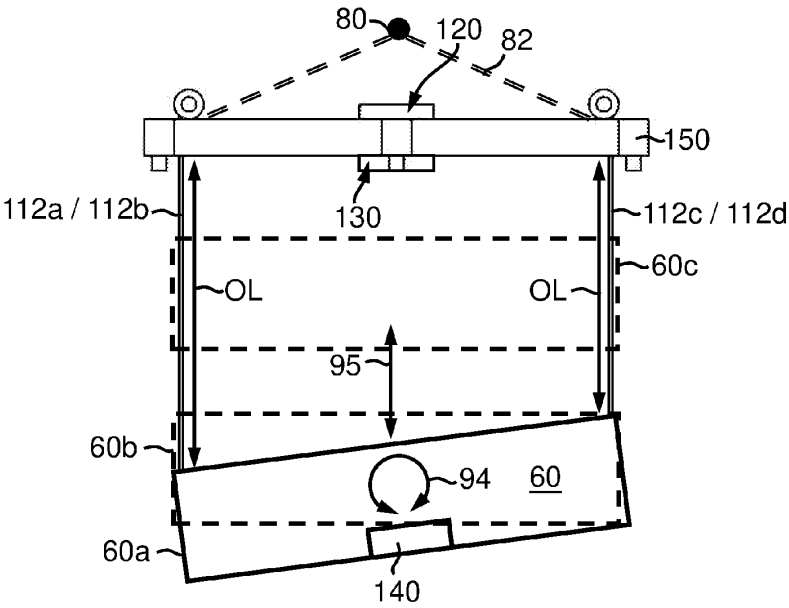
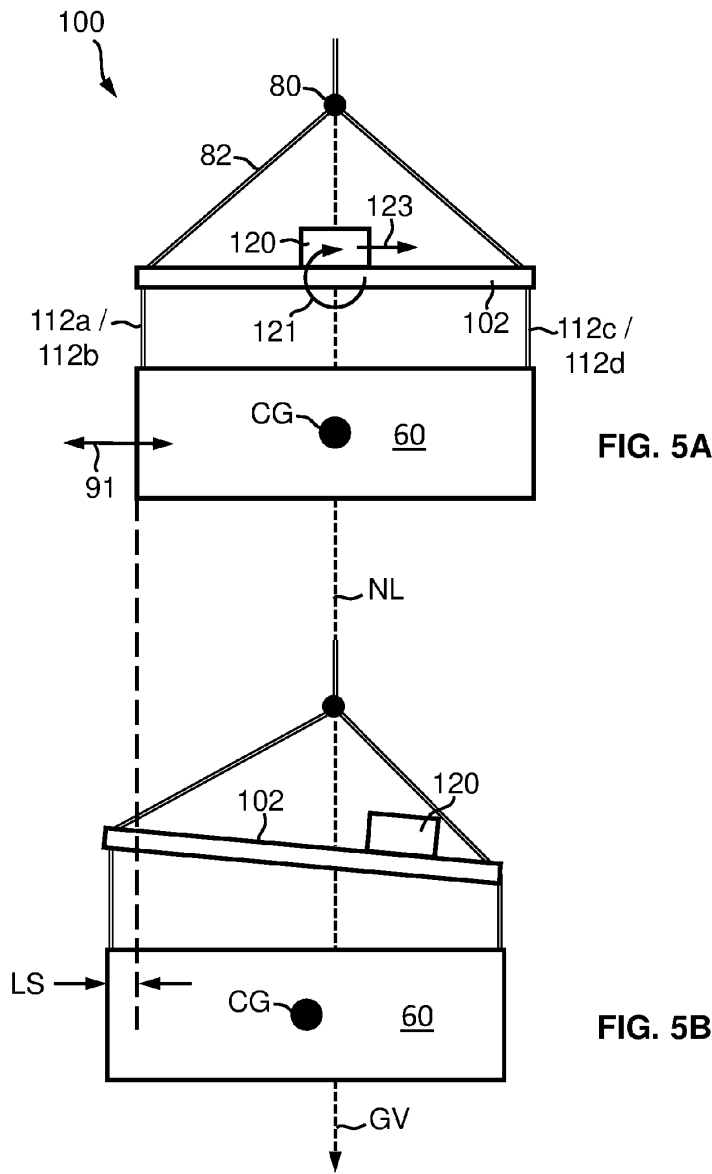


FIG. 4B



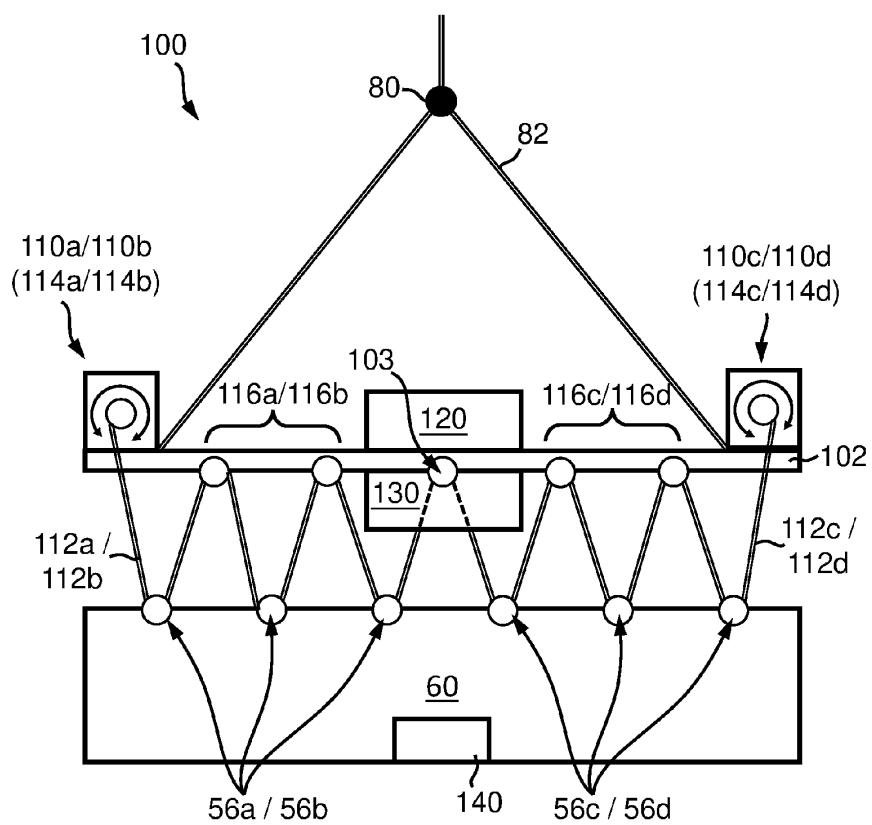


FIG. 6

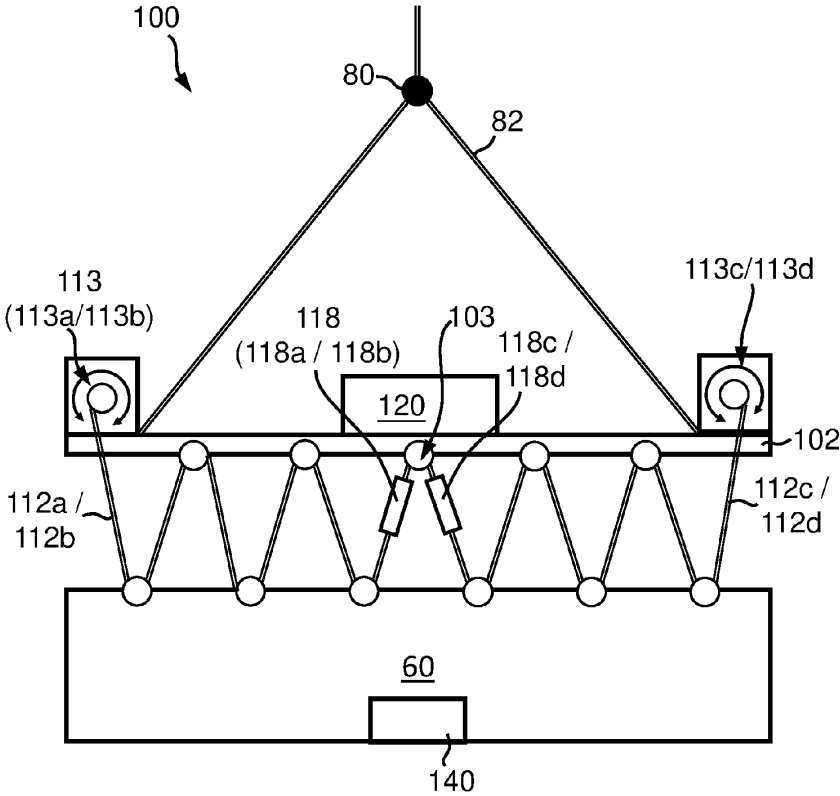


FIG. 7A

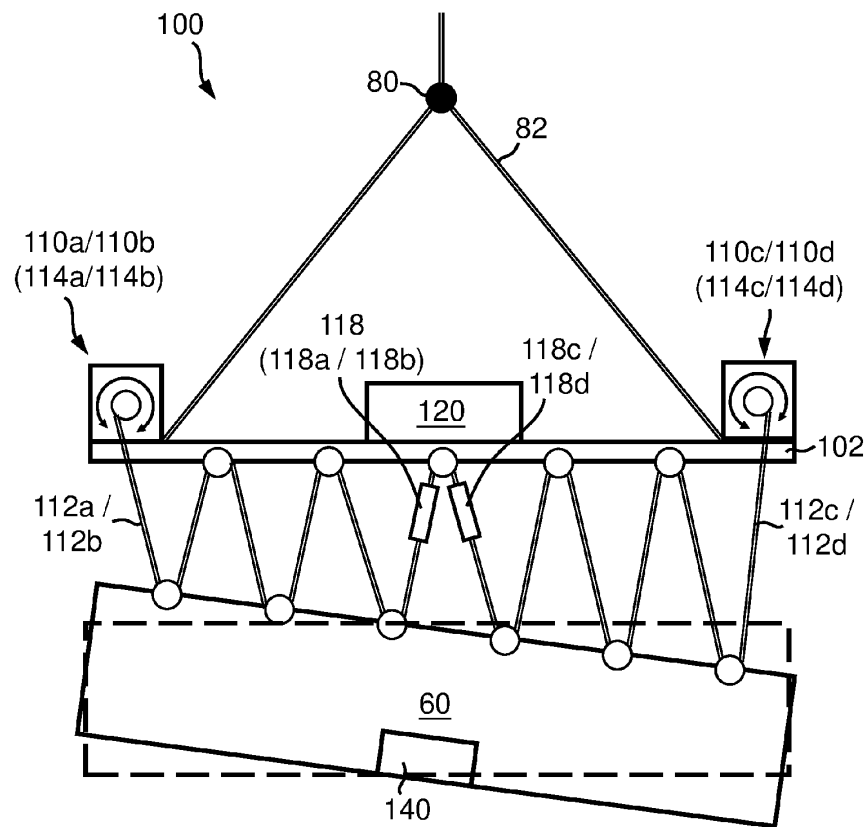


FIG. 7B

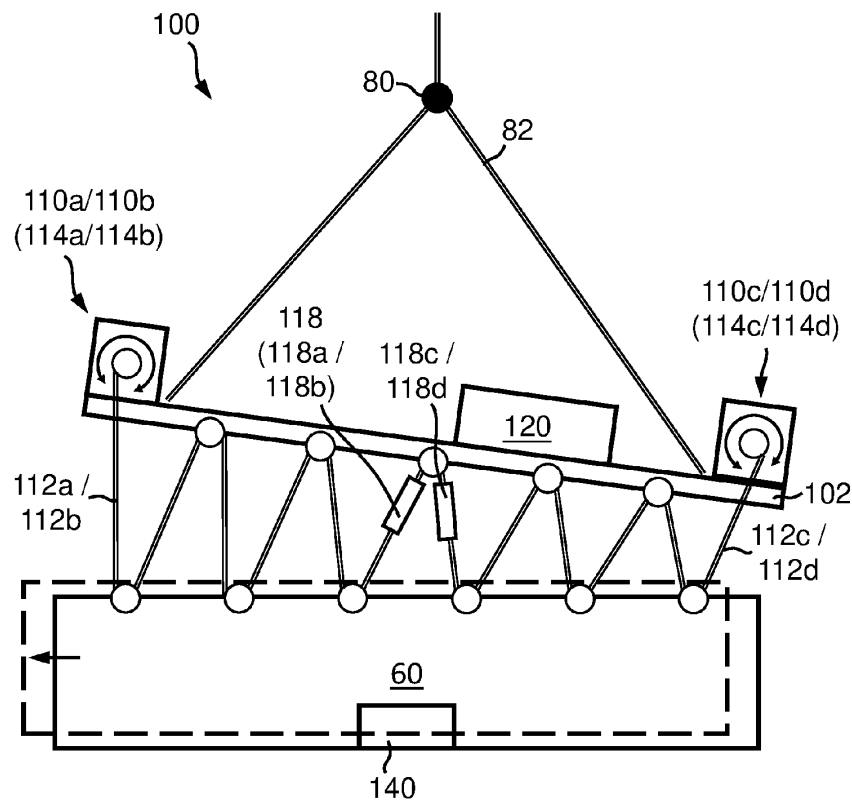


FIG. 7C

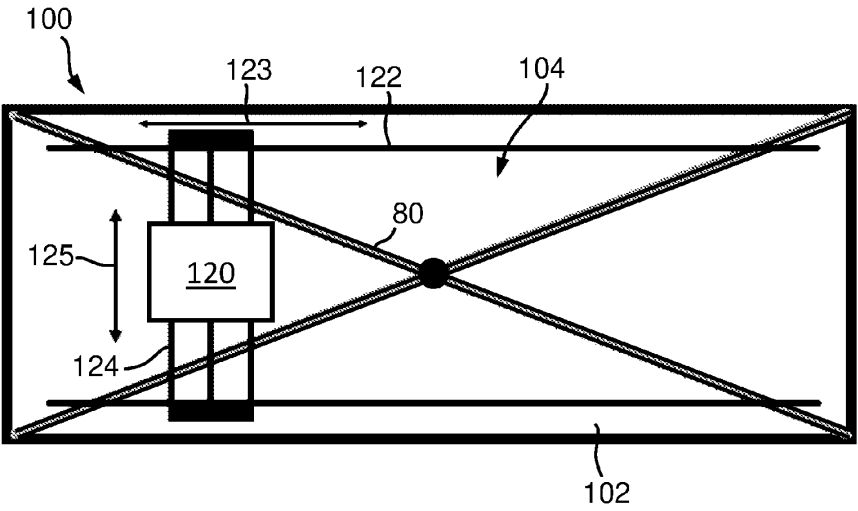


FIG. 8

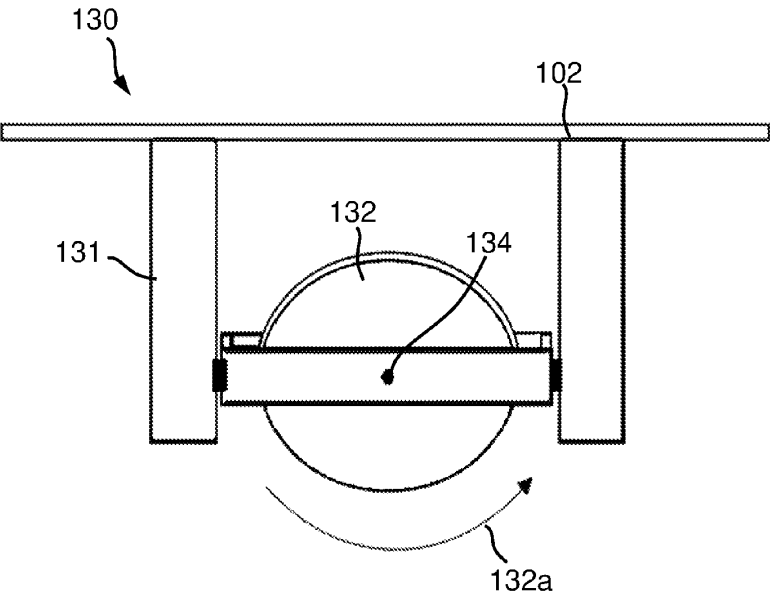


FIG. 9

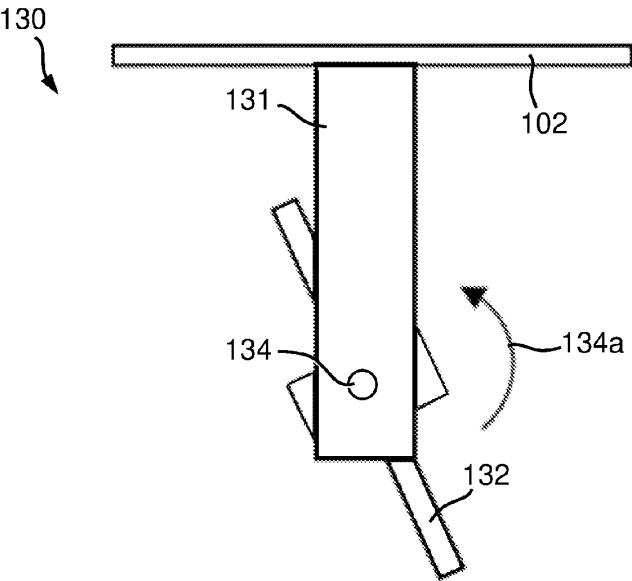


FIG. 10

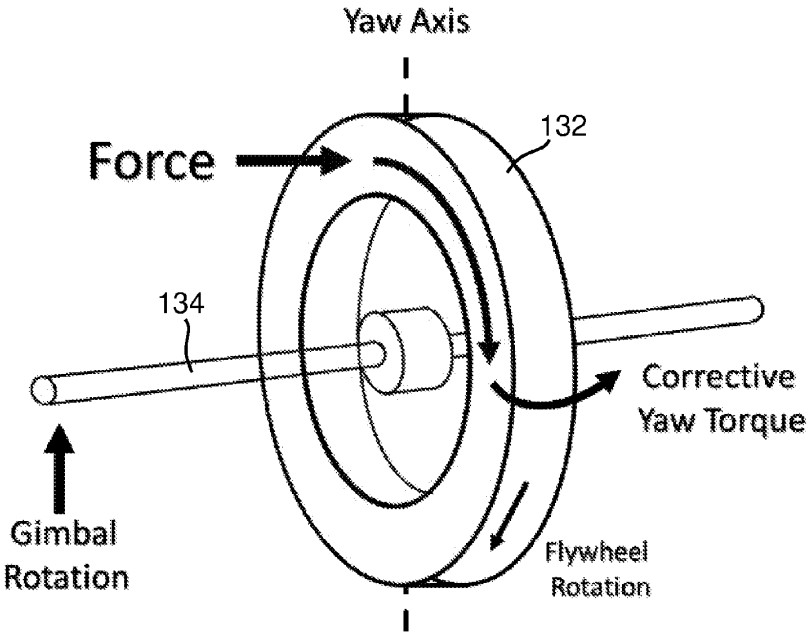


FIG. 11

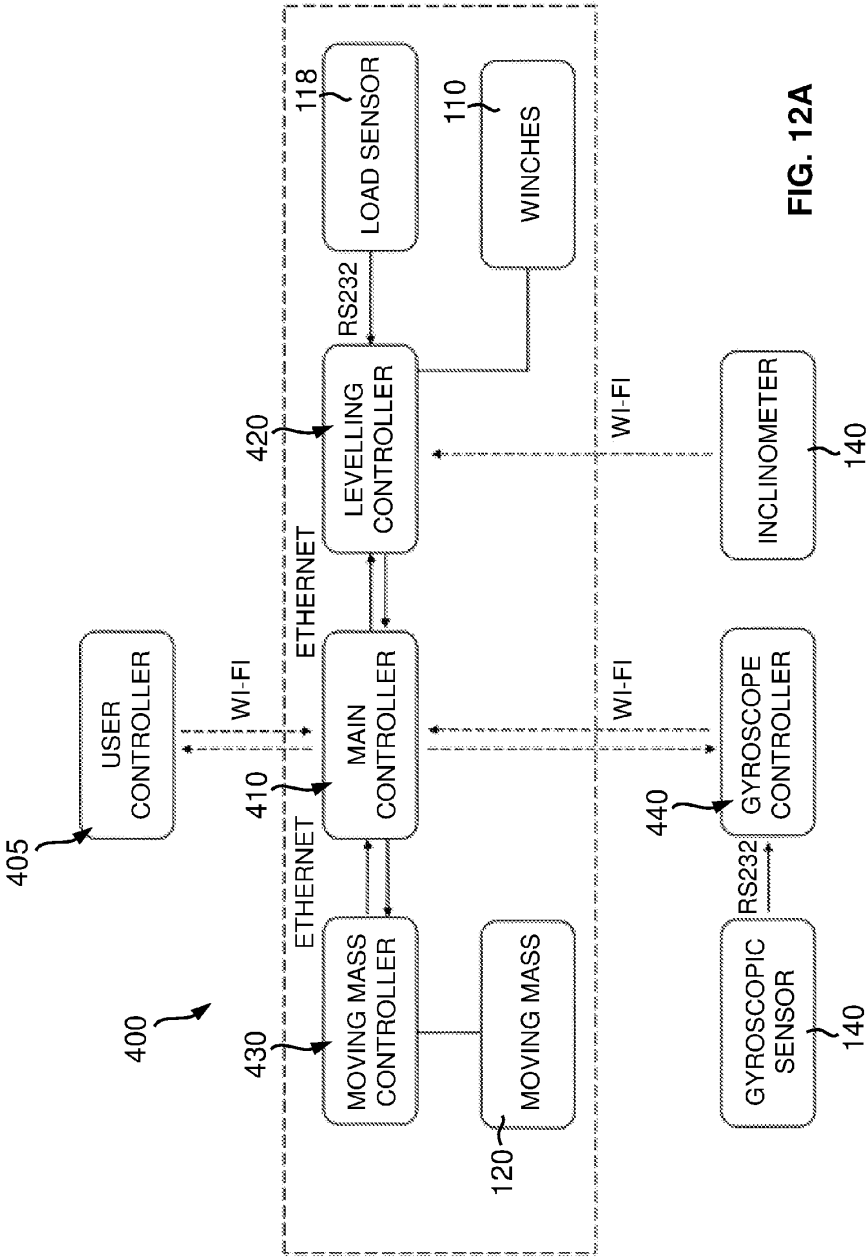


FIG. 12A

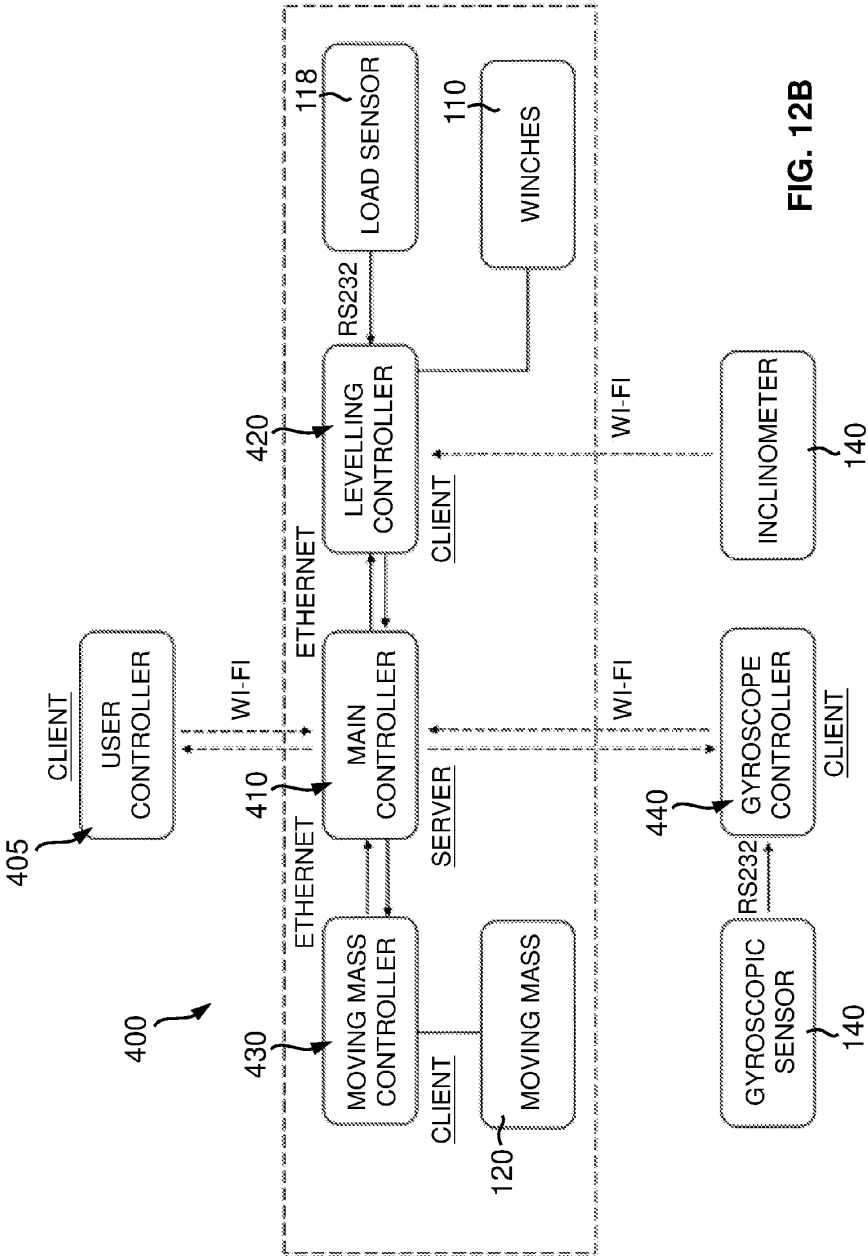


FIG. 12B

Lifting Frame Control Board

Horizontal Adjustment

X

(-1000~1000)

Y

(-250~250)

H-stop

Set

Move

☒ With Levelling

Target Pos

X

Current Pos

Y

Moving Mass Info

Current

Task:

Moving Mass

Gyro

Levelling

E-STOP

Yaw Adjustment

Stabilizer On

Stabilizer Off

Zero

Gyro Stop

Up

Vertical Adjustment

Up

Initialize

Winch 1

Winch 2

Winch 3

Winch 4

Keep Levelling

(mm)

Down

Levelling

Step

(e.g. 00150 for up 150 steps)

(e.g. 10150 for down 150 steps)

Load 1

Load 2

Load 3

Load 4

Roll

Pitch

Tilt Info

Battery

Load Info

Message:

Send Message

Server IP

192.168.1.6

Port

8080

Connect

Disconnect

Clear

FIG. 13

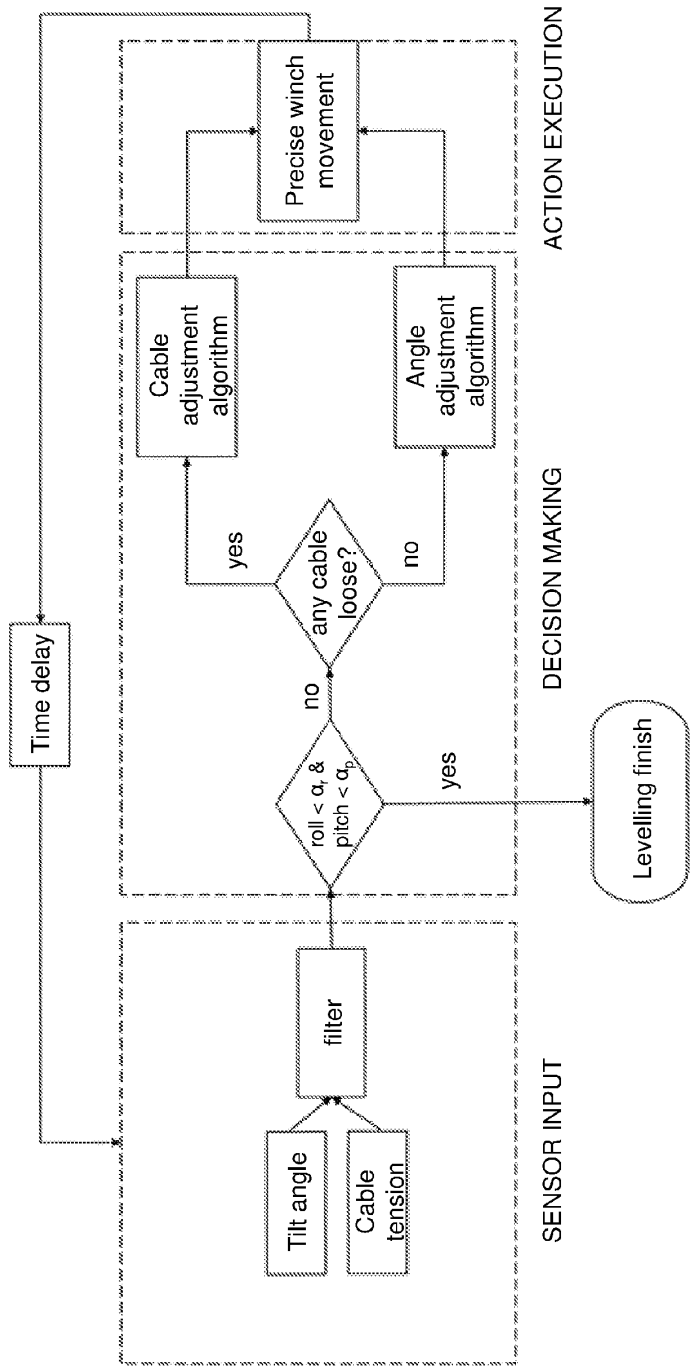


FIG. 14

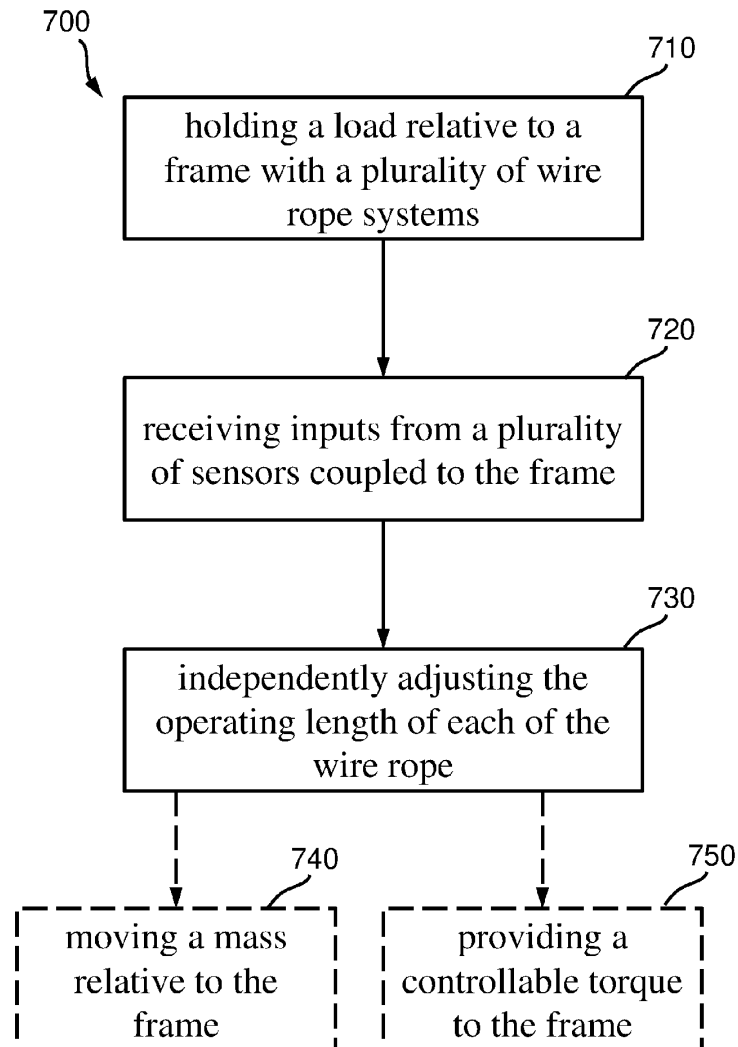


FIG. 15

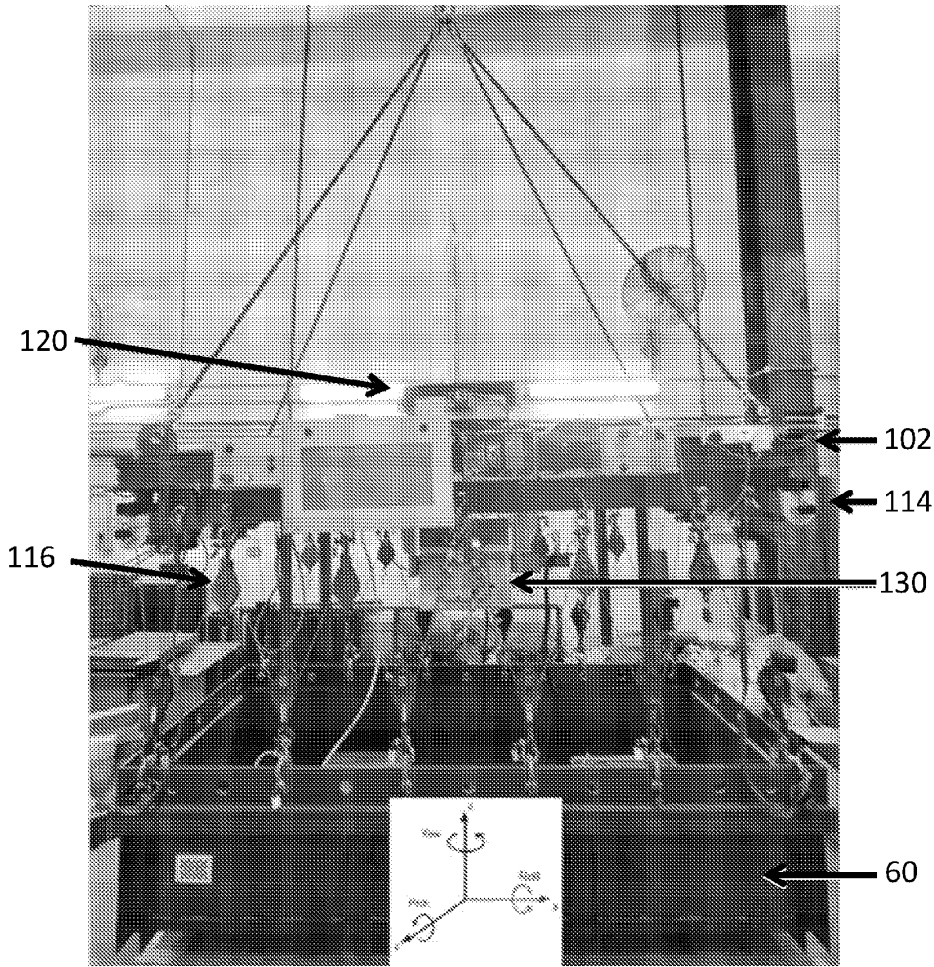


FIG. 16

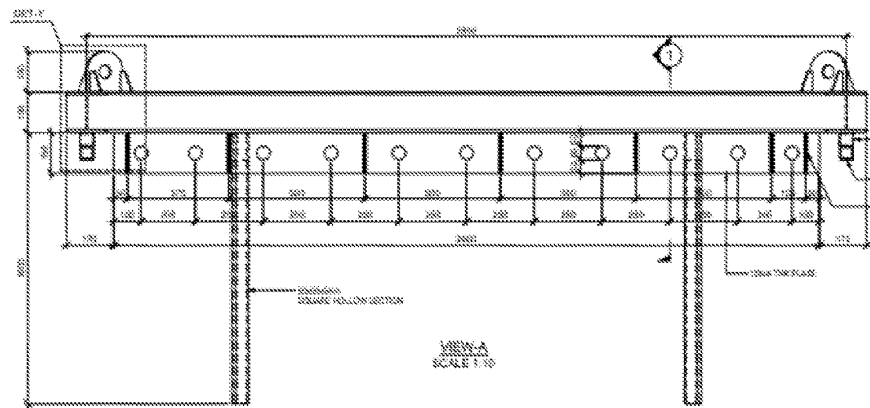


FIG. 17A



FIG. 17B

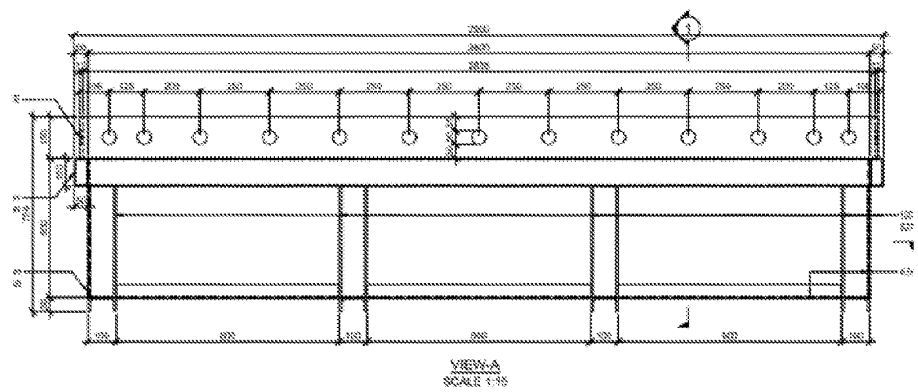


FIG. 18A

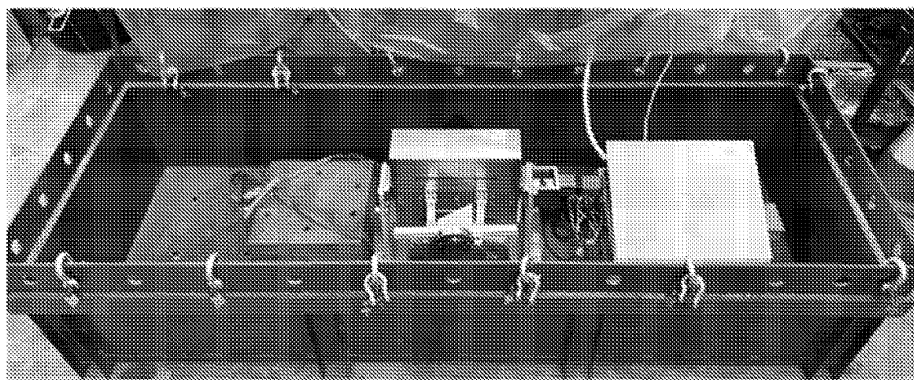


FIG. 18B

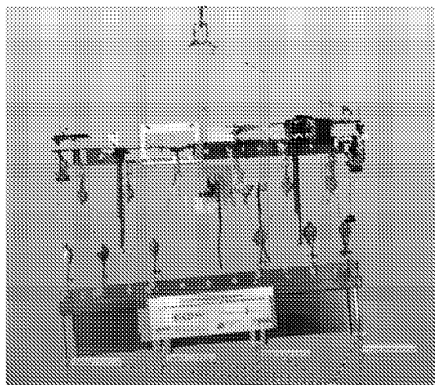


FIG. 19A

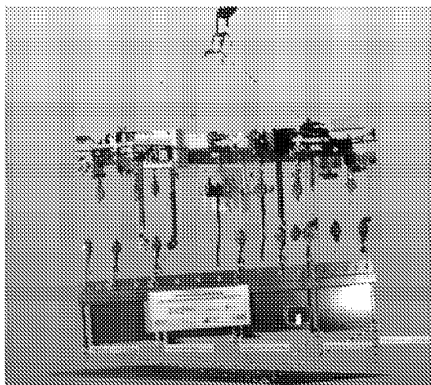


FIG. 19B

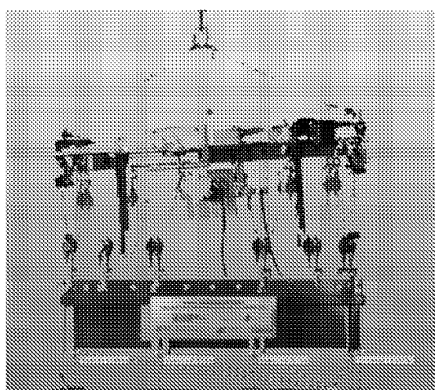


FIG. 19C

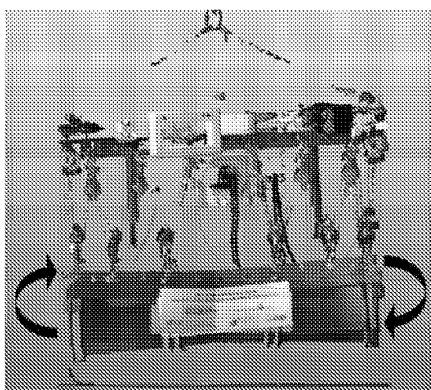


FIG. 19D

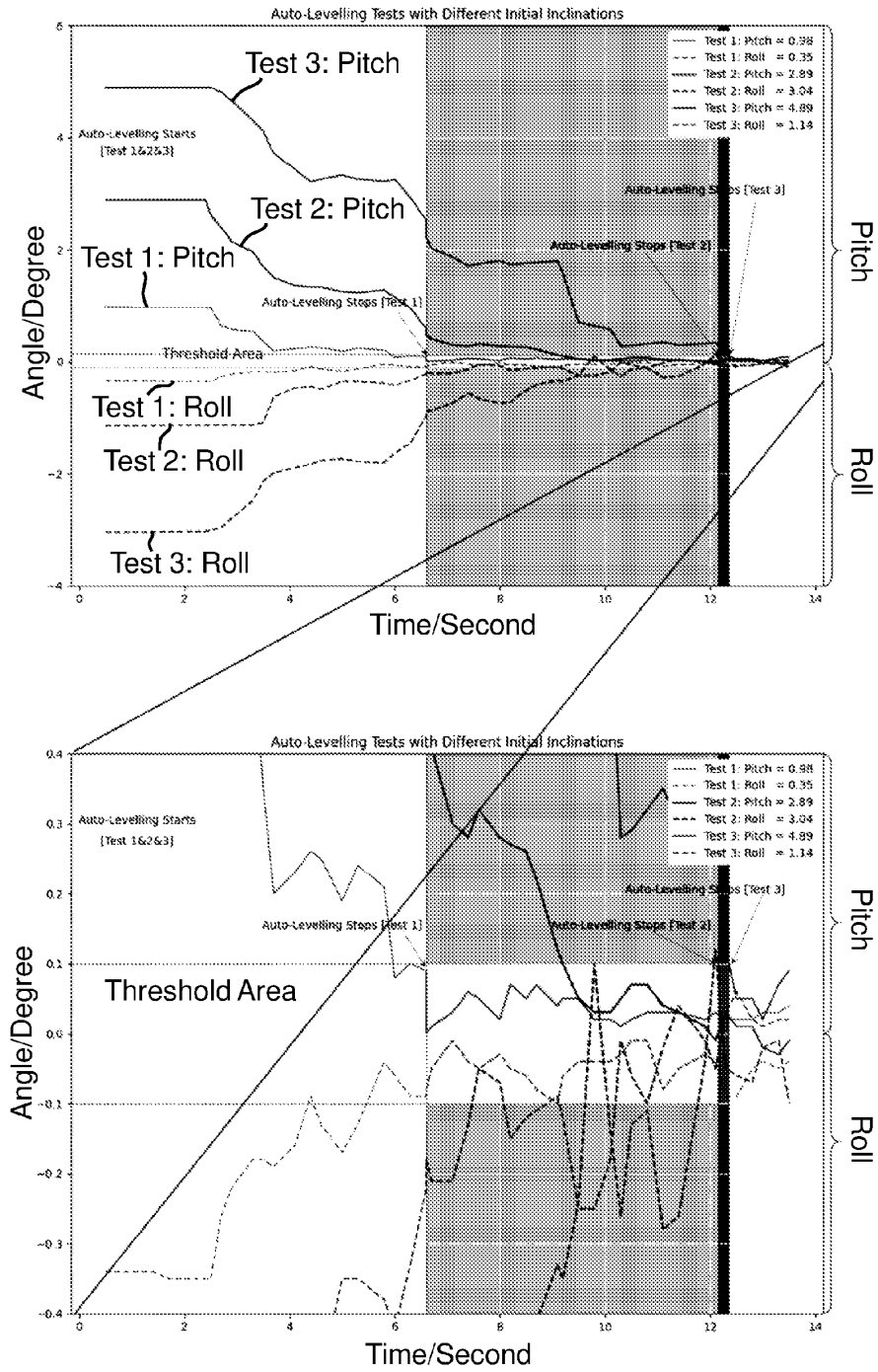


FIG. 20

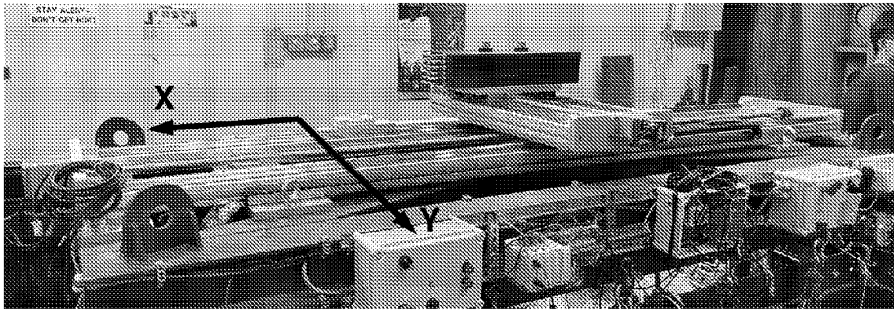


FIG. 21

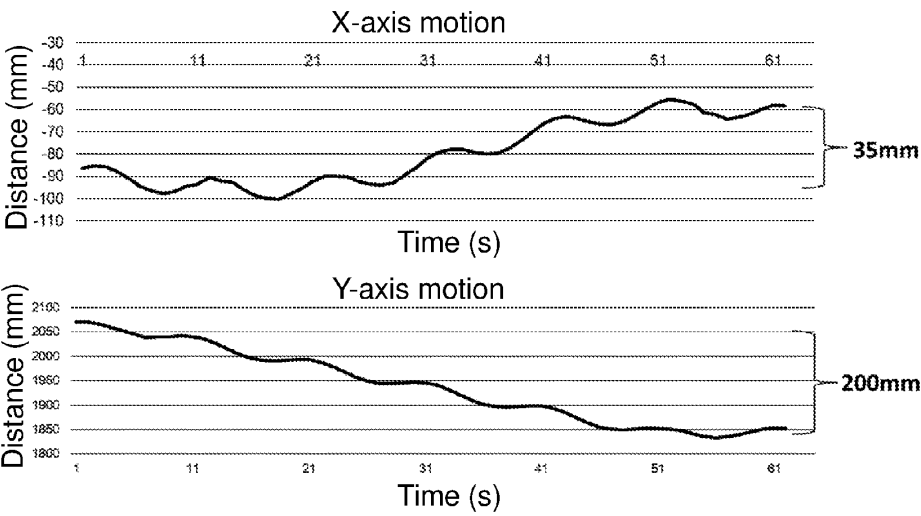


FIG. 22

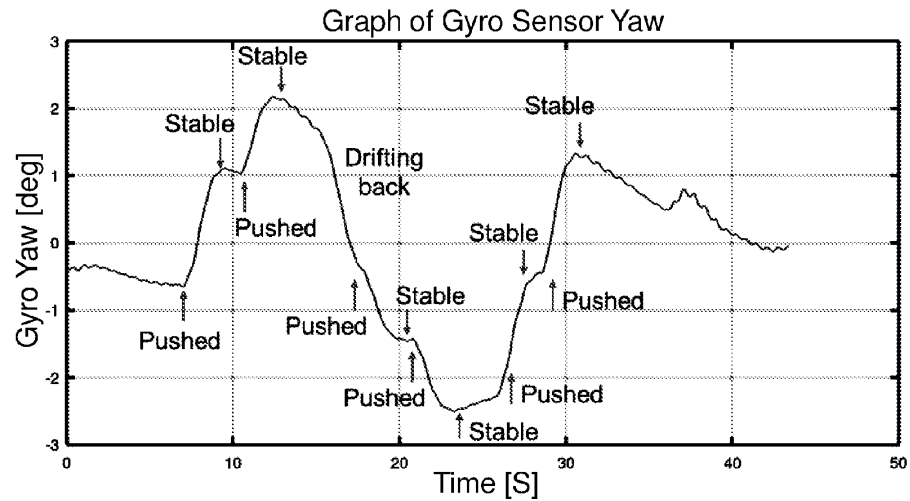
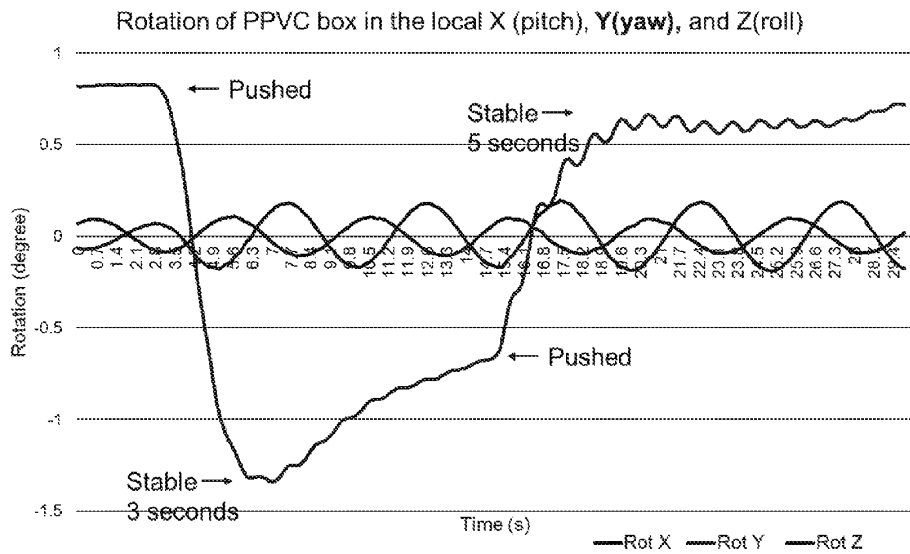


FIG. 23



*measured deviations, using a 0.1 second recording frequency

FIG. 24

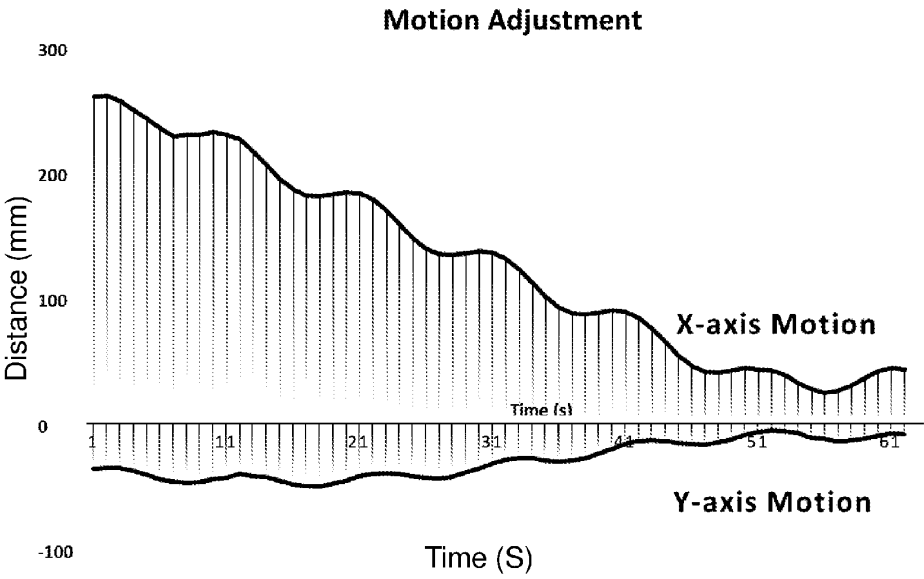


FIG. 25

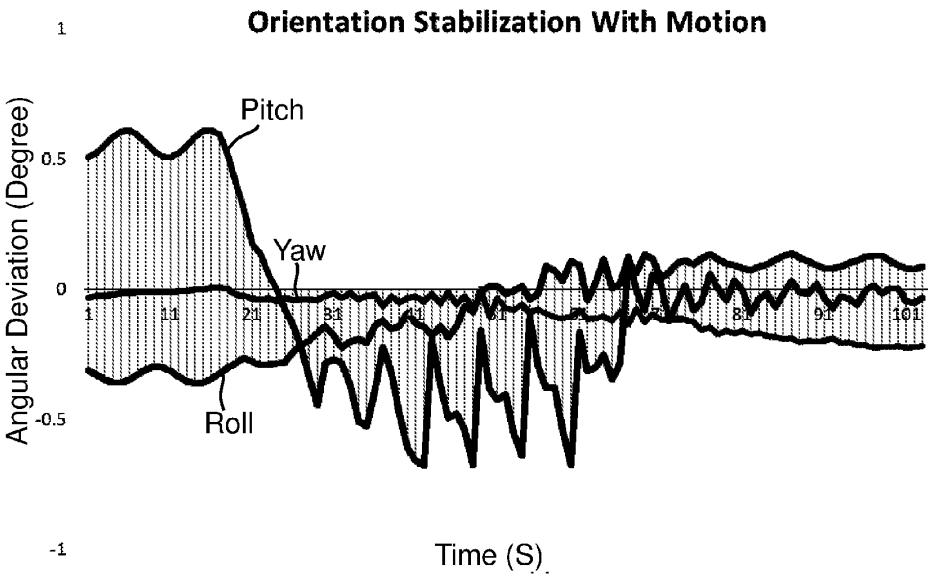


FIG. 26