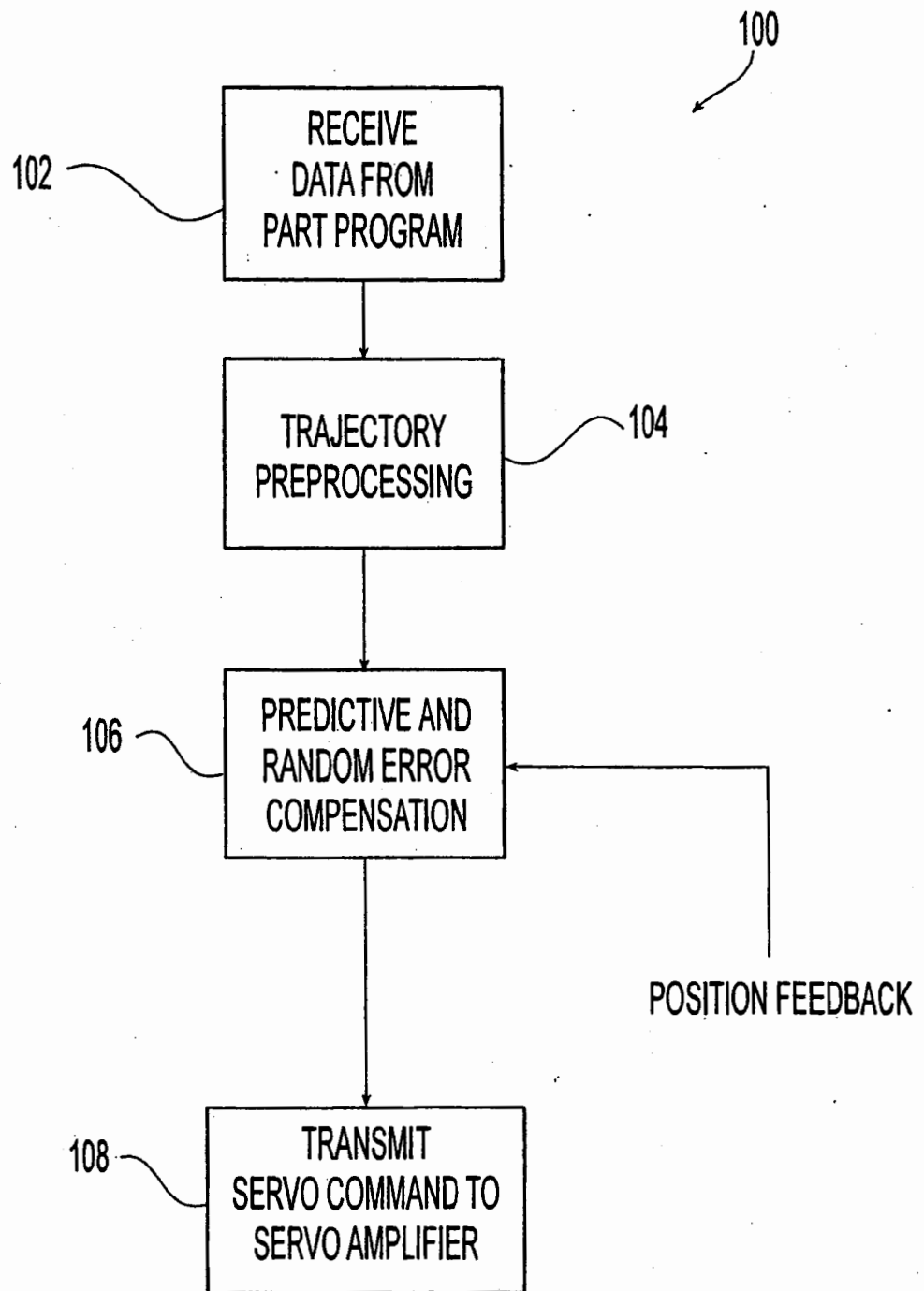


*Fig. 1*

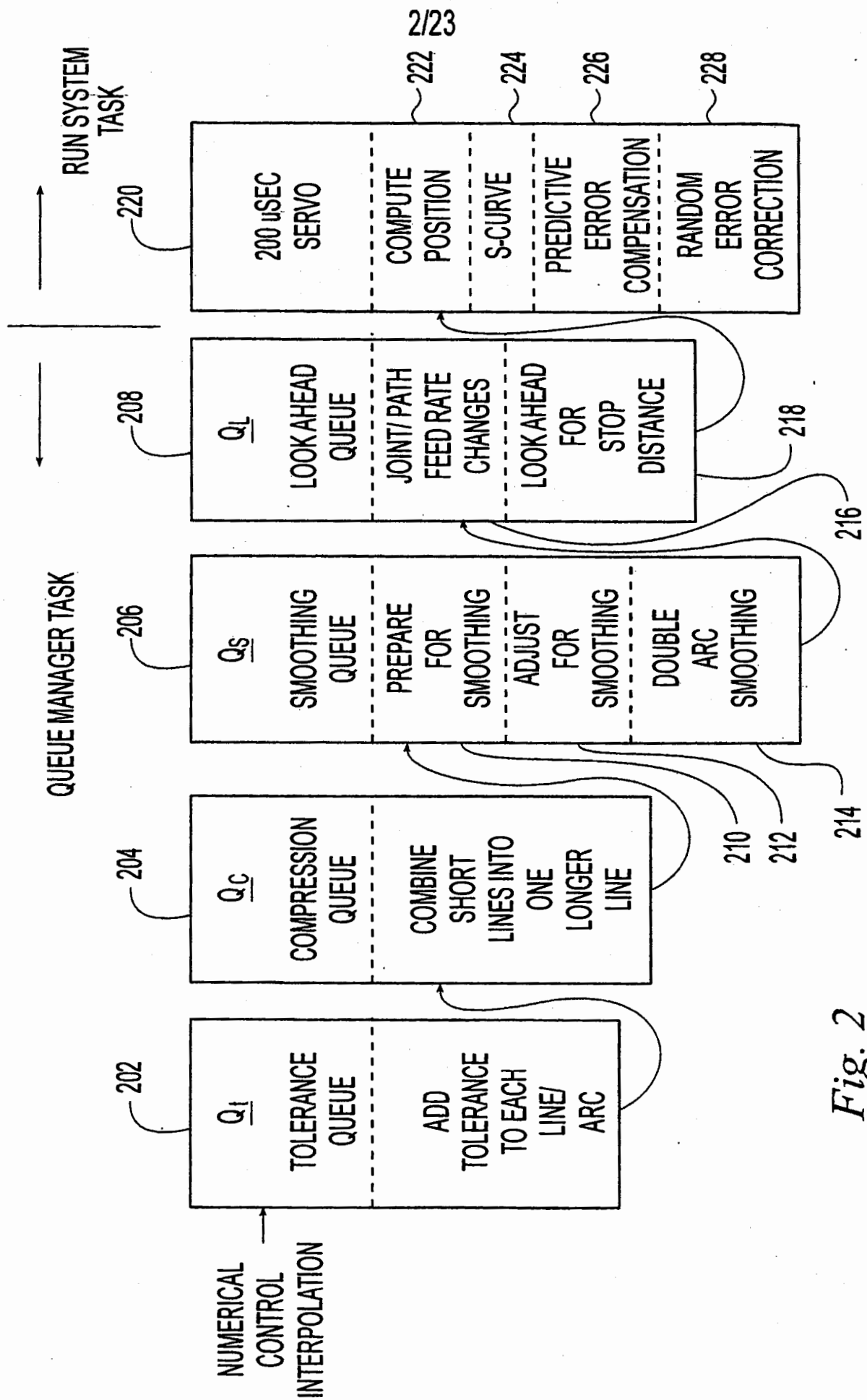


Fig. 2

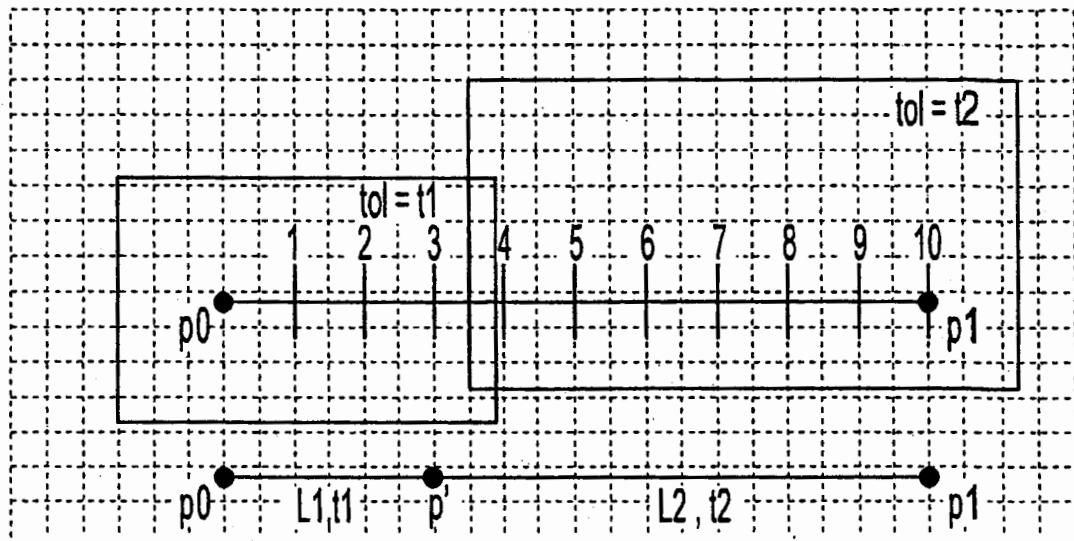


Fig. 3a

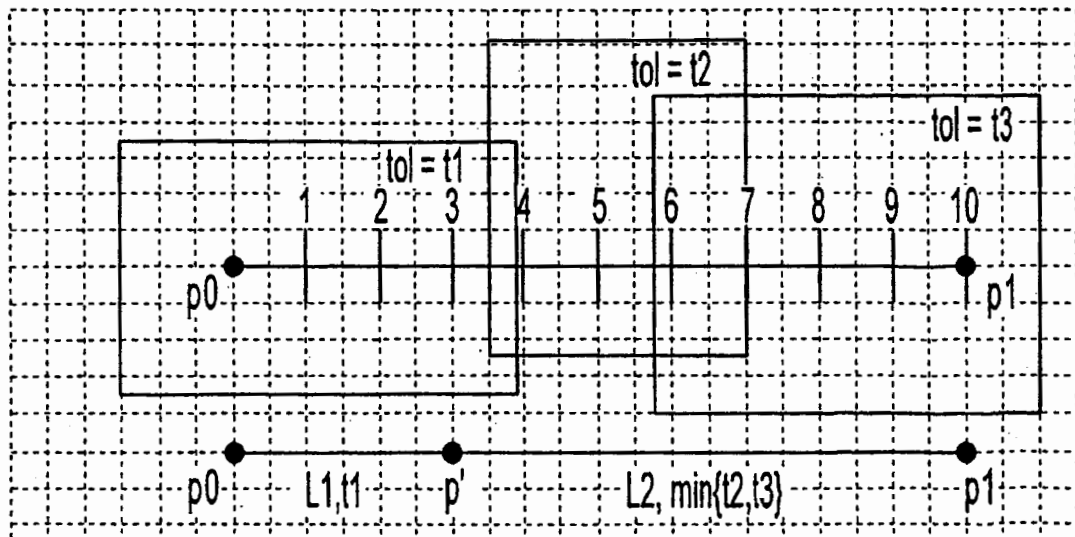


Fig. 3b

$$\text{tol} = \min \{t_1, t_2, t_3, t_4, t_5\}$$

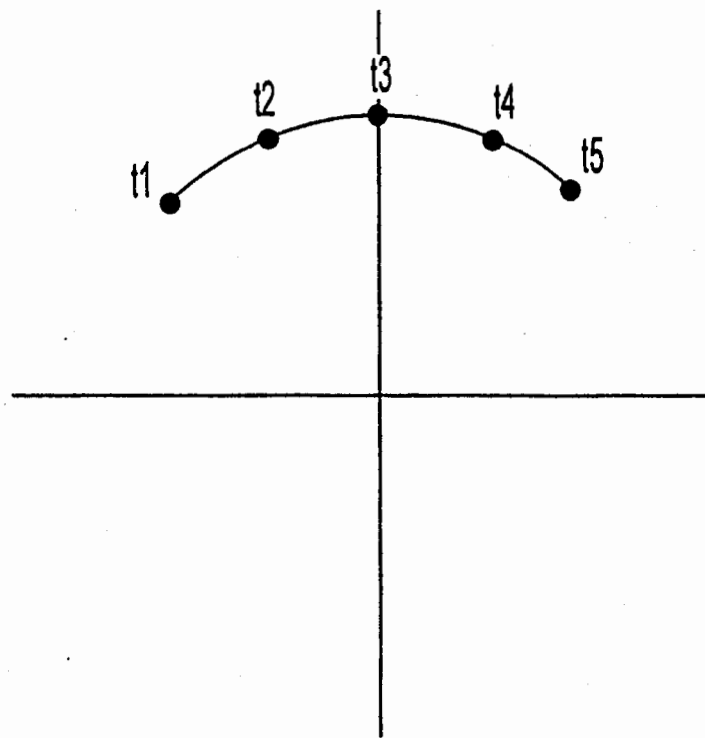
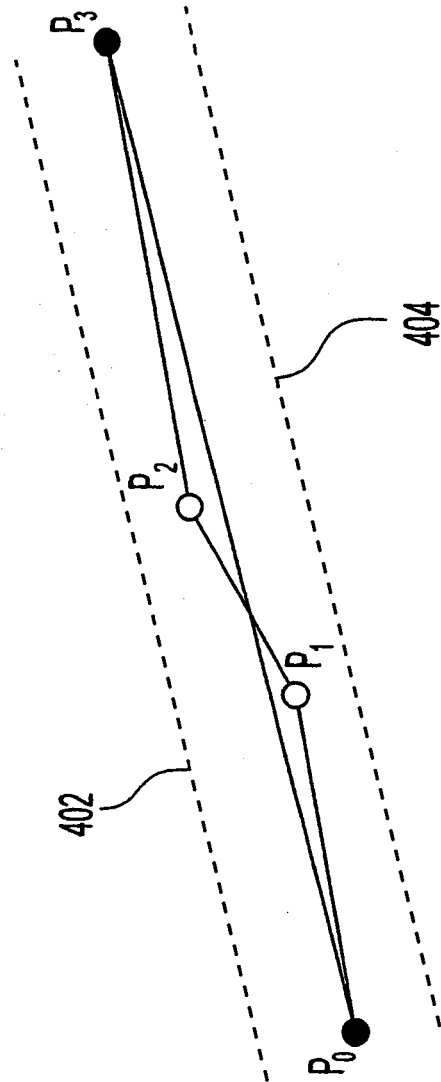
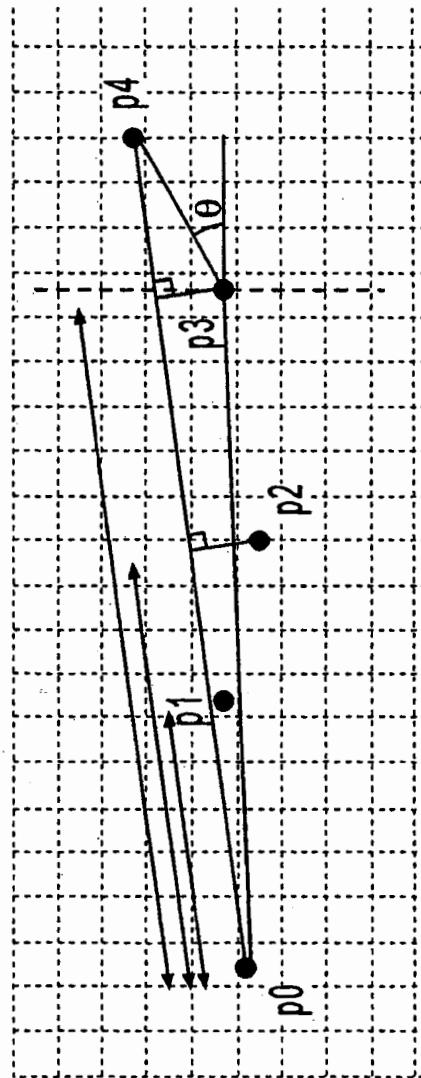


Fig. 3c

*Fig. 4a*

*Fig. 4b*

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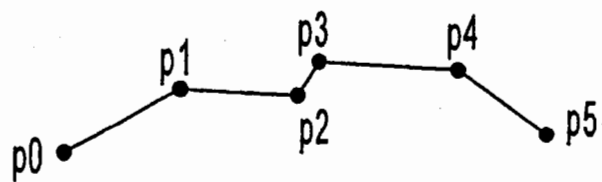


Fig. 5a

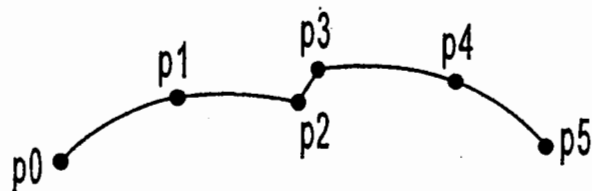


Fig. 5b

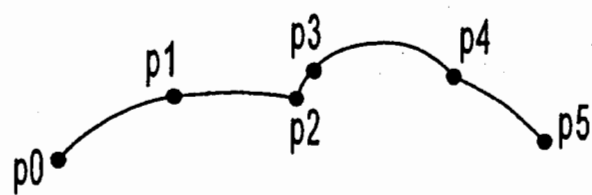


Fig. 5c

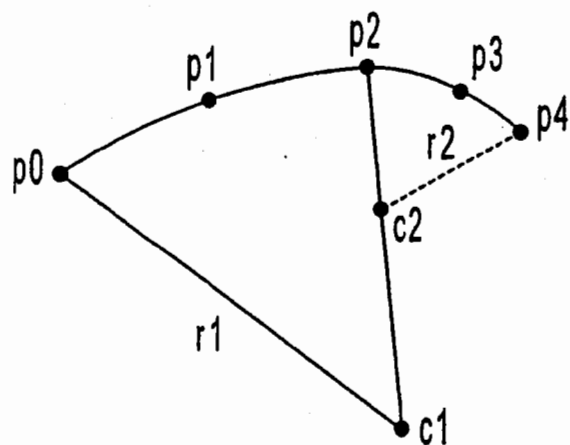


Fig. 5d

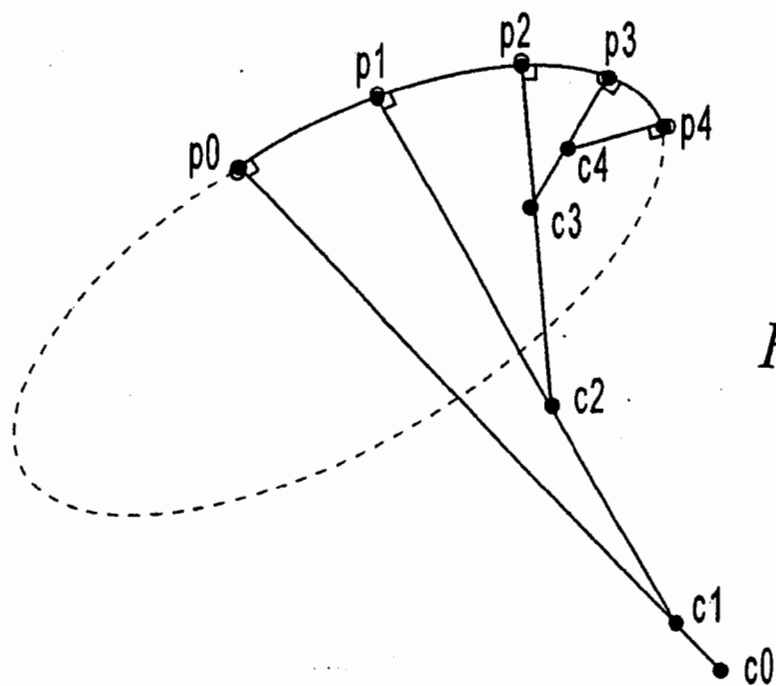
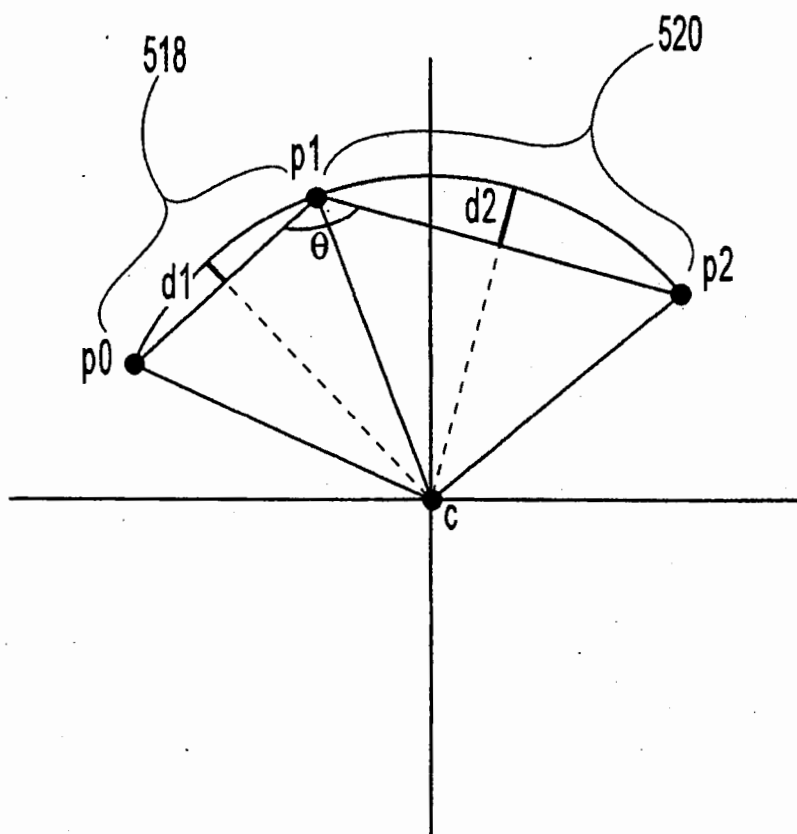
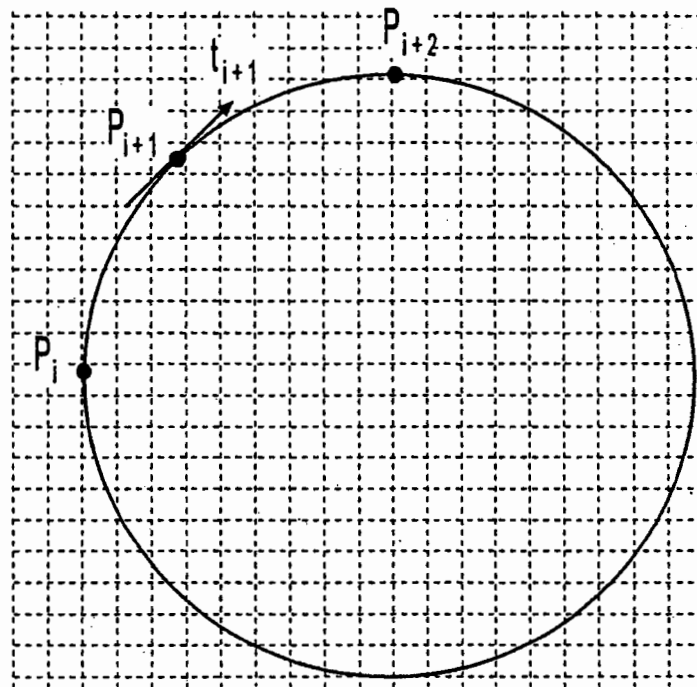


Fig. 5e

*Fig. 6*

*Fig. 8*

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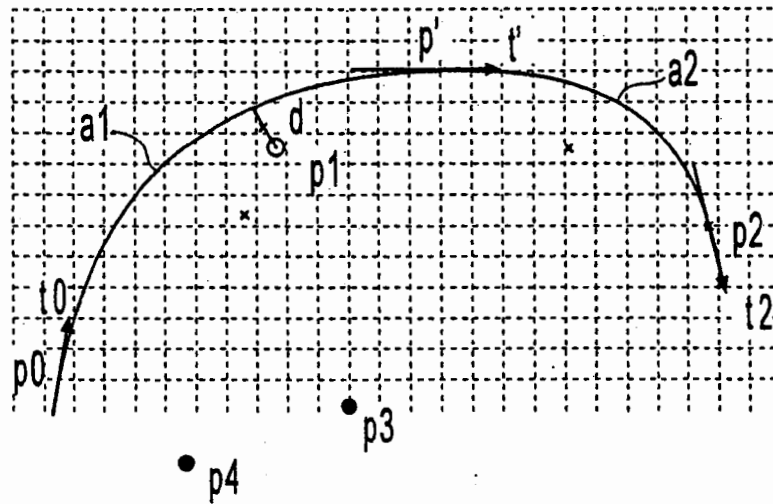


Fig. 9

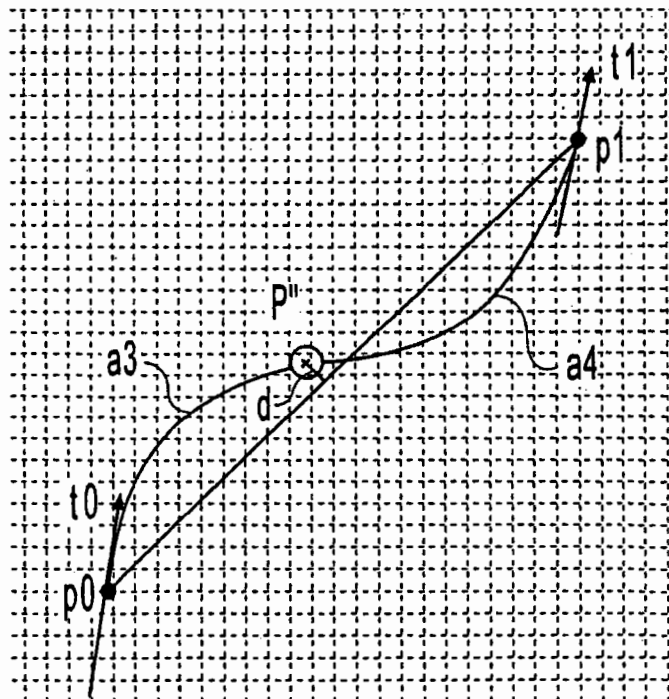


Fig. 10

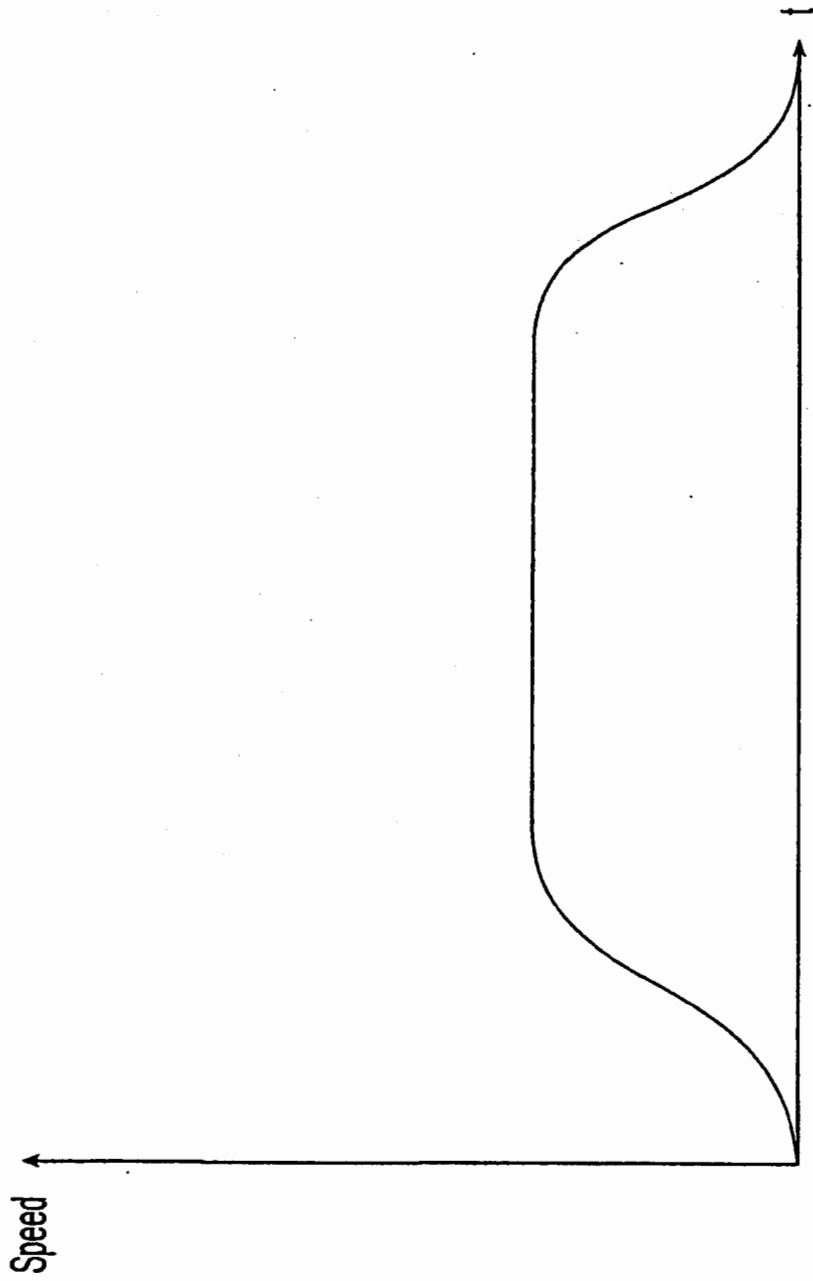
*Fig. 11*

Fig. 12a

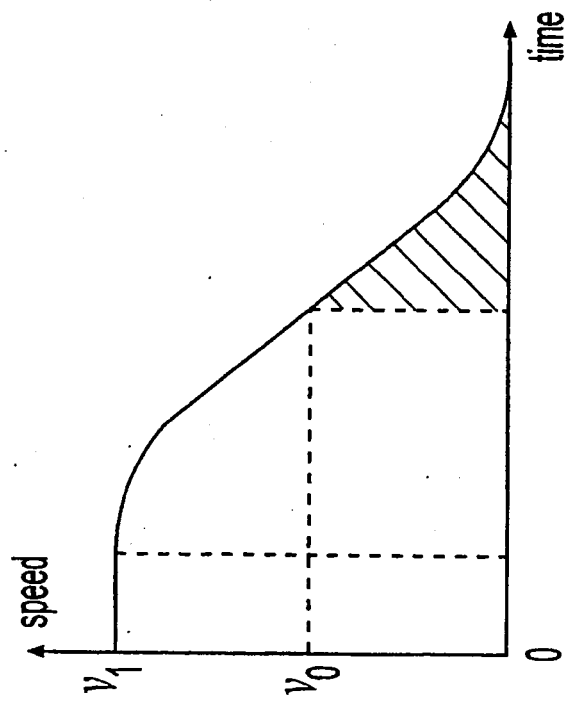
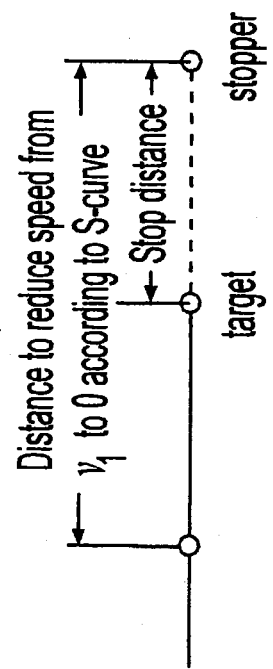


Fig. 12b



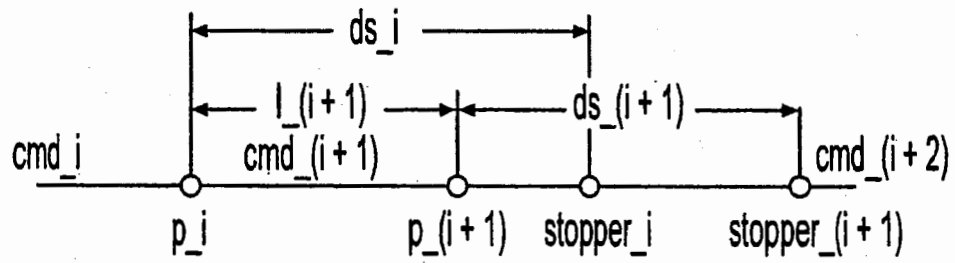


Fig. 13

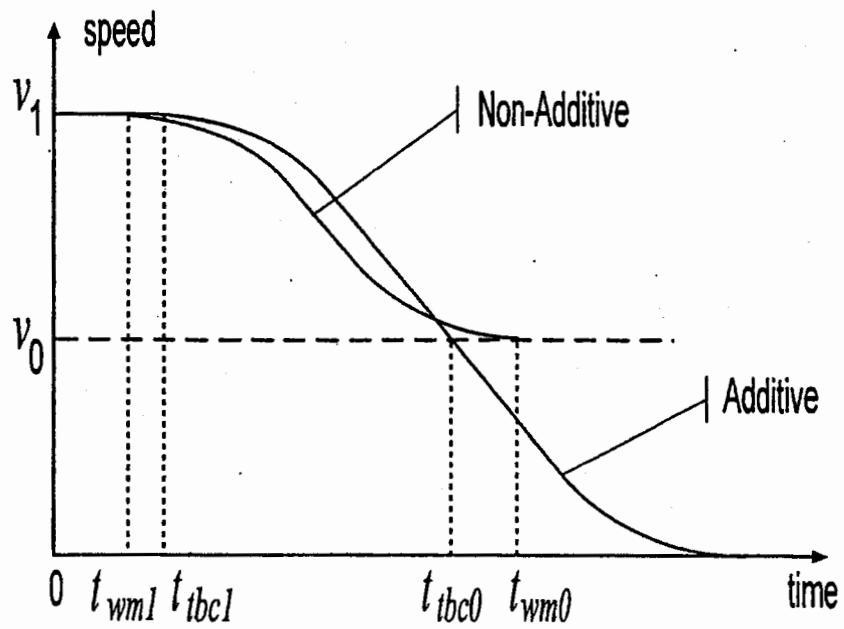
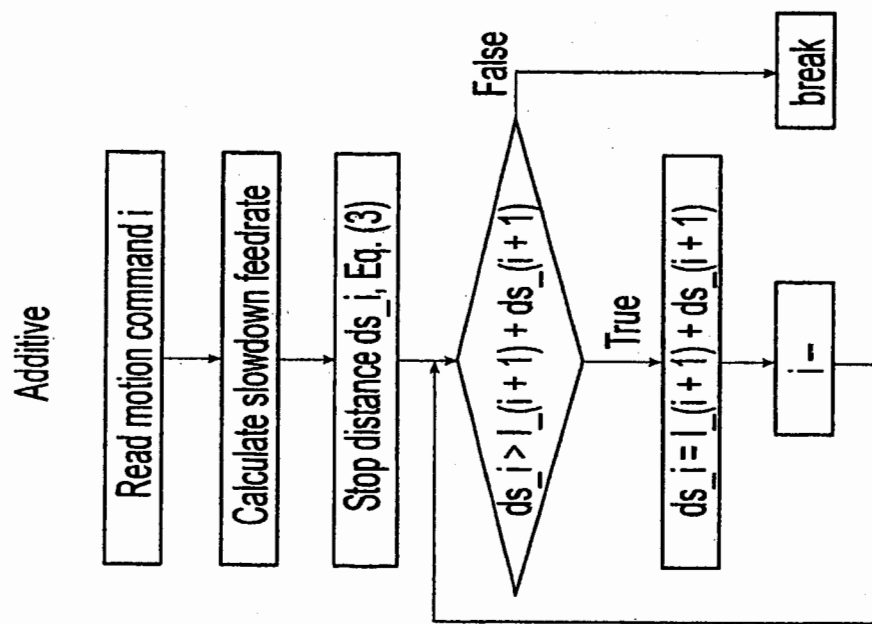


Fig. 14

*Fig. 15*

Non - TBC Motion Control

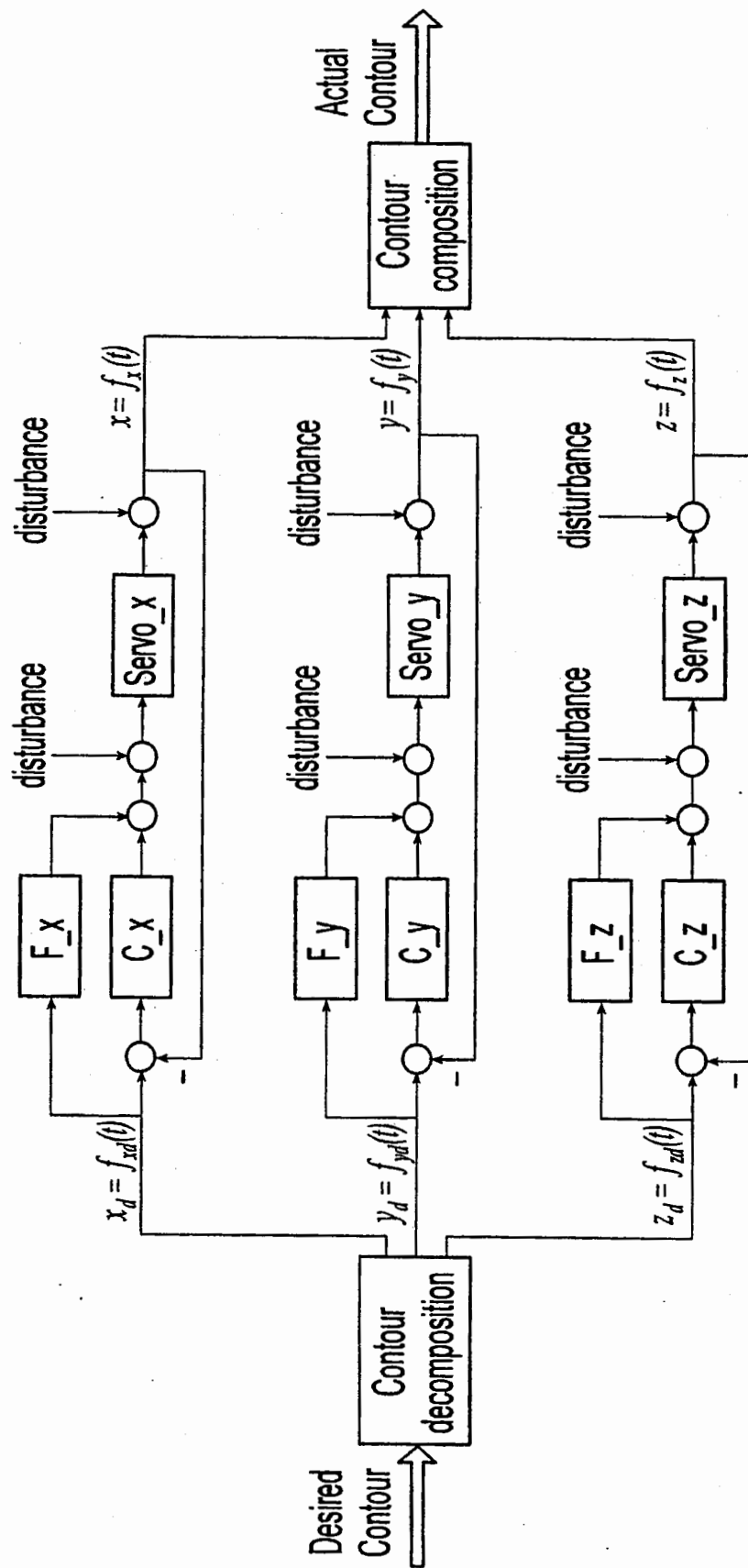
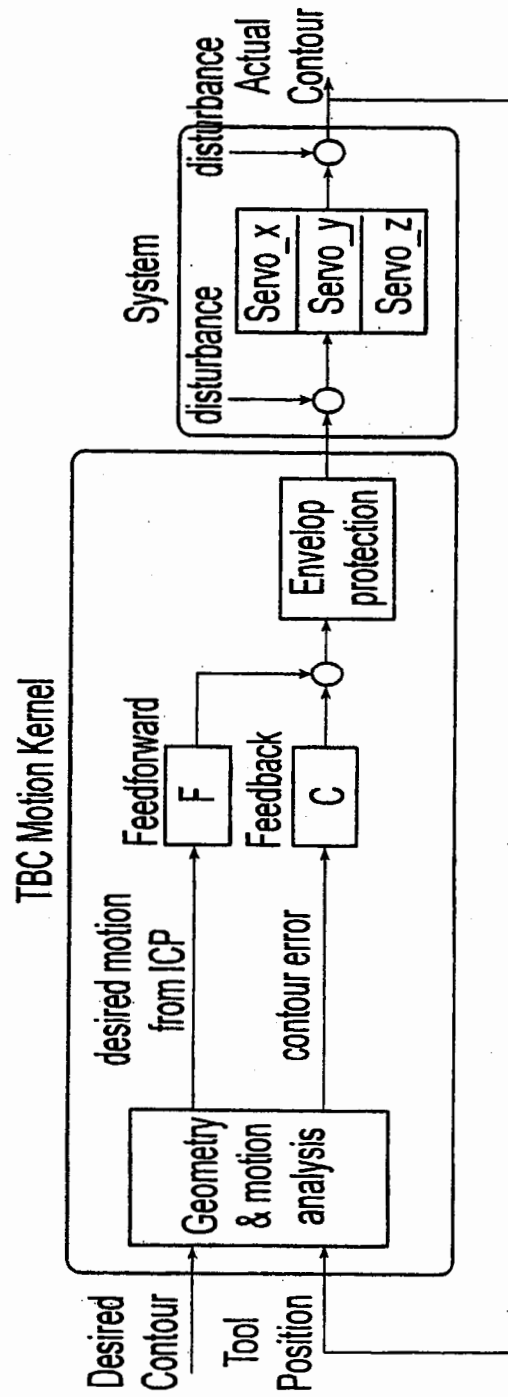


Fig. 16

*Fig. 17*

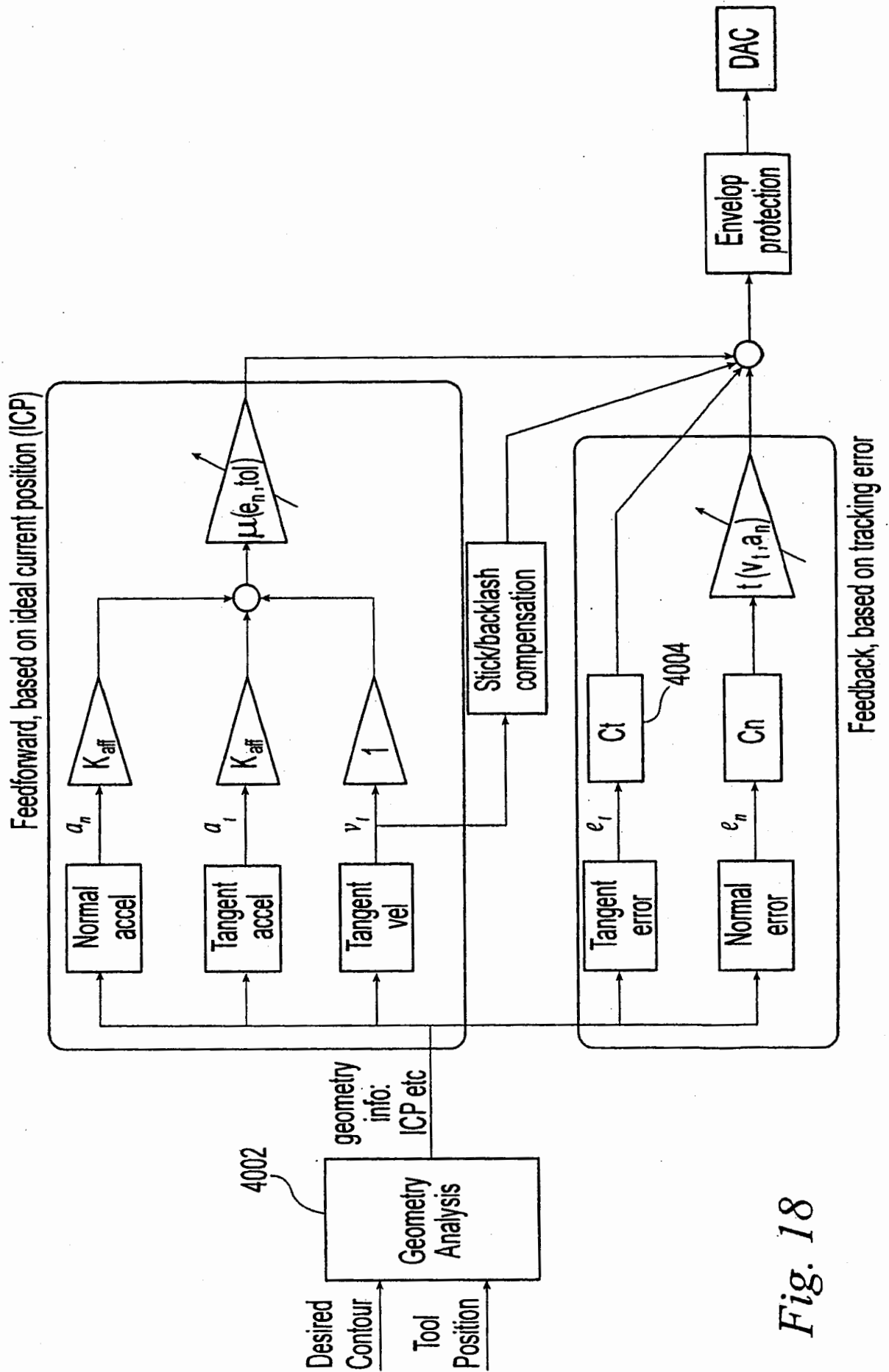


Fig. 18

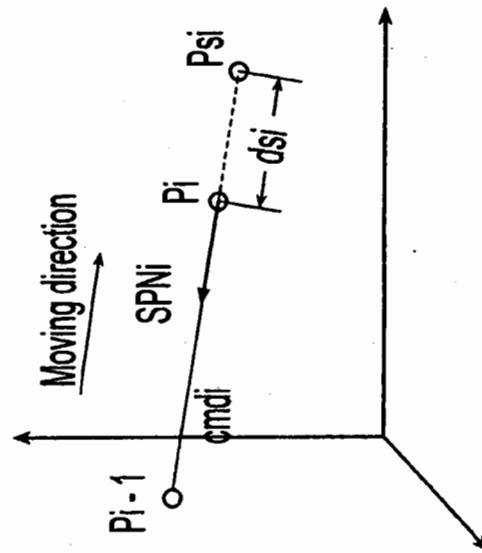


Fig. 19

Fig. 20

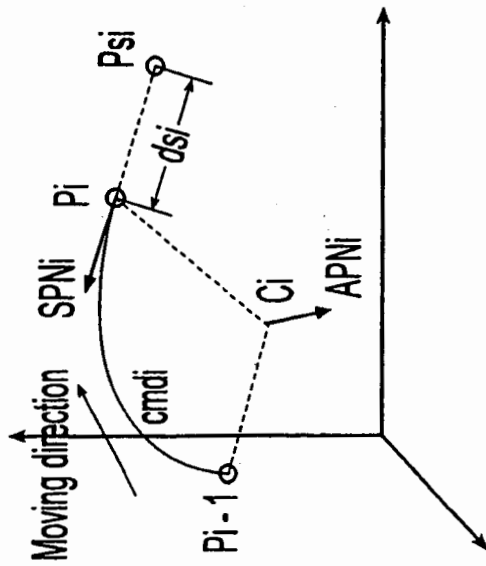
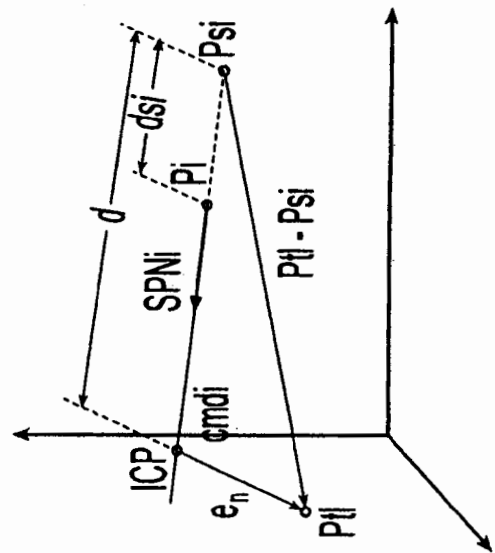
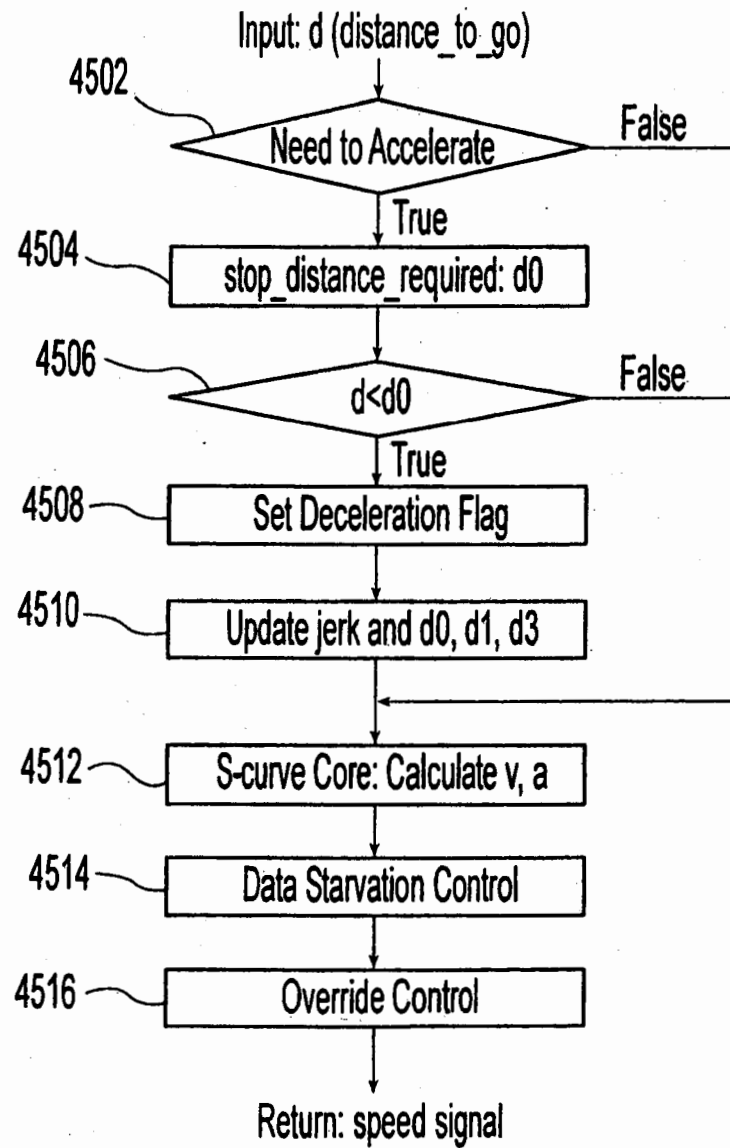


Fig. 21



*Fig. 23*

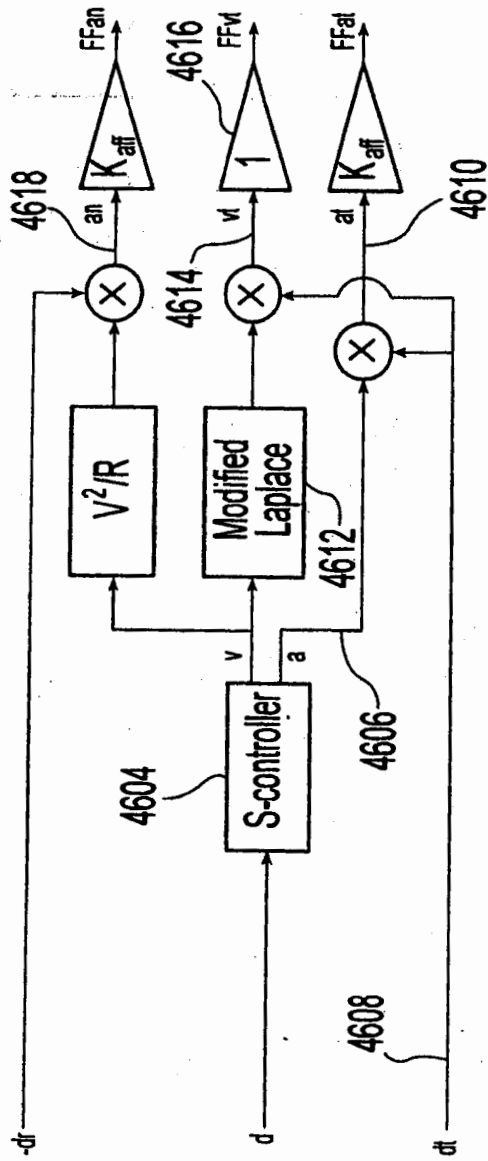


Fig. 24

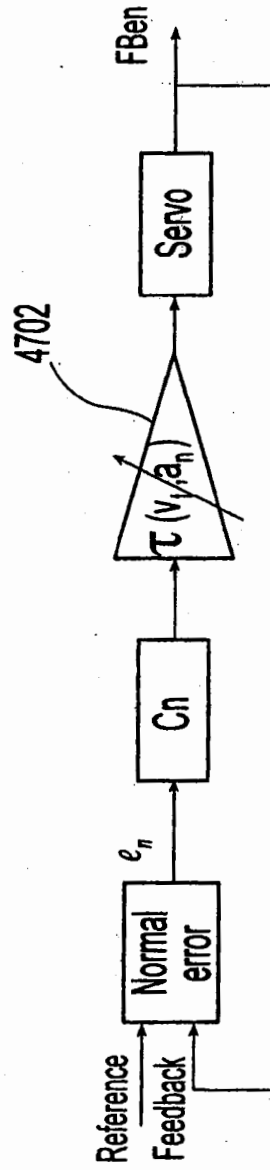


Fig. 25