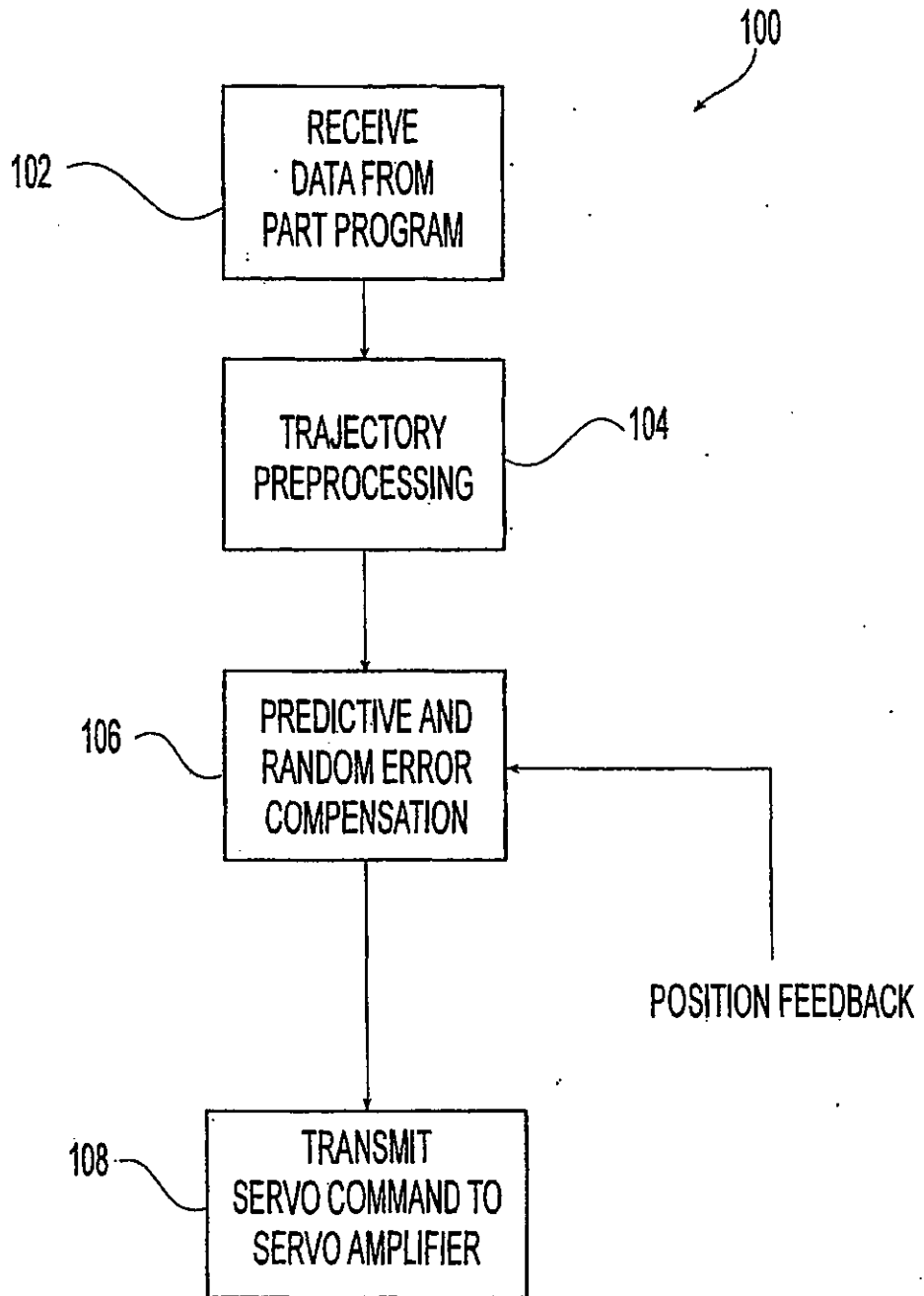


*Fig. 1*

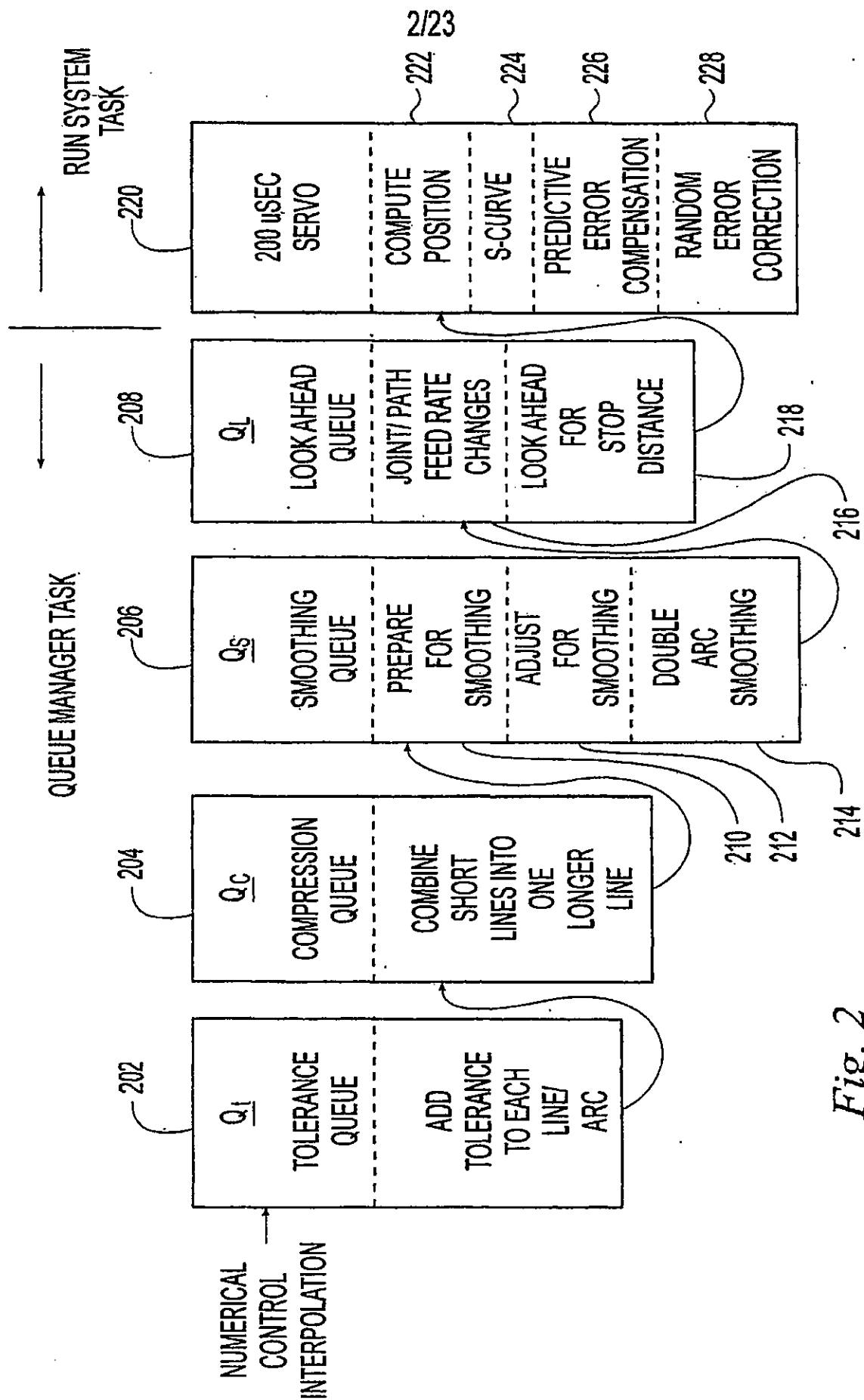


Fig. 2

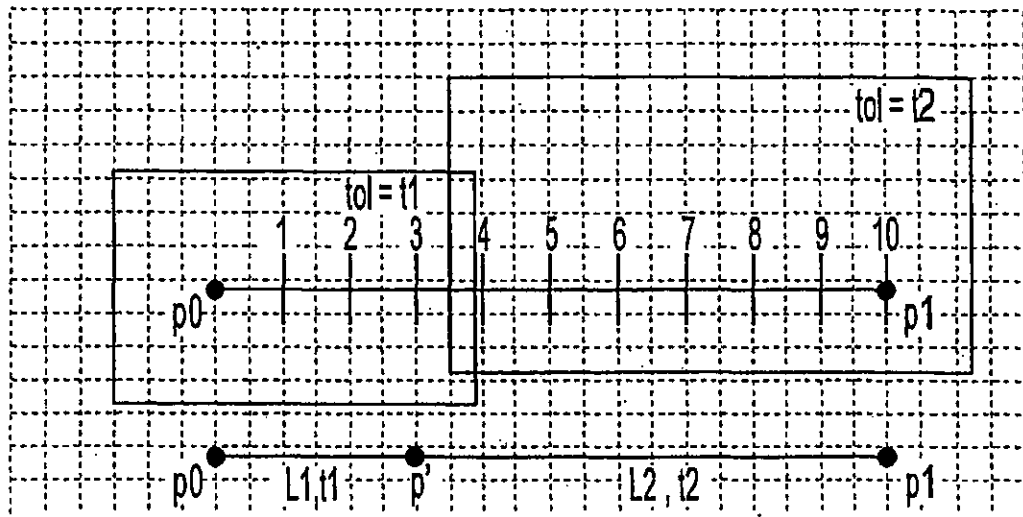


Fig. 3a

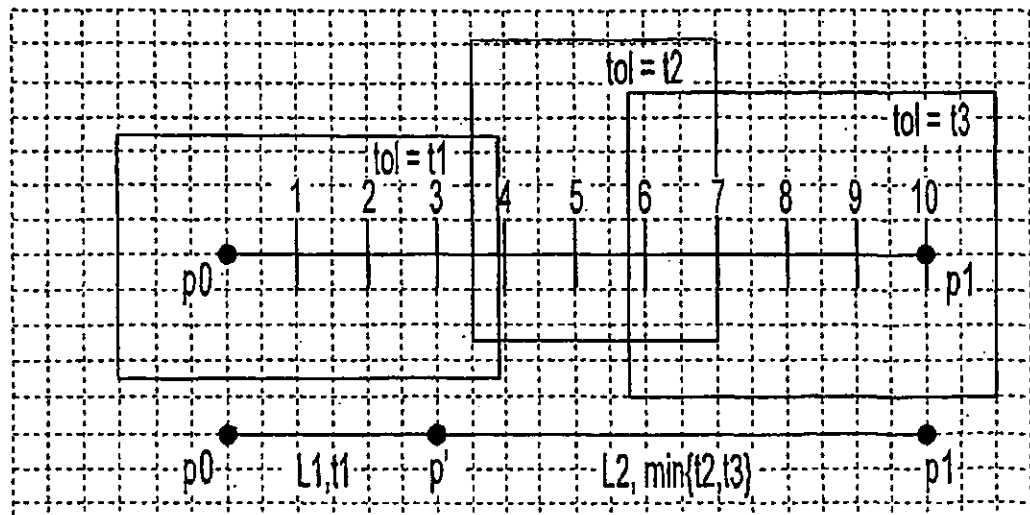


Fig. 3b

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

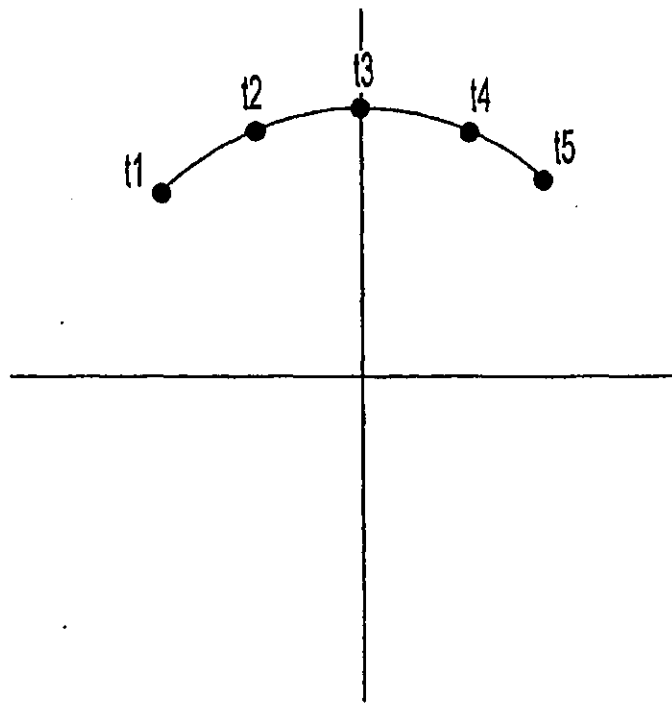
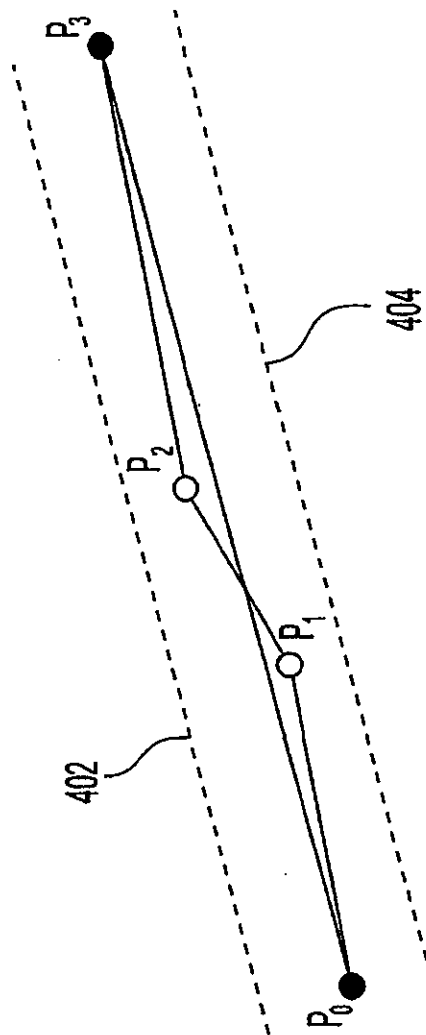
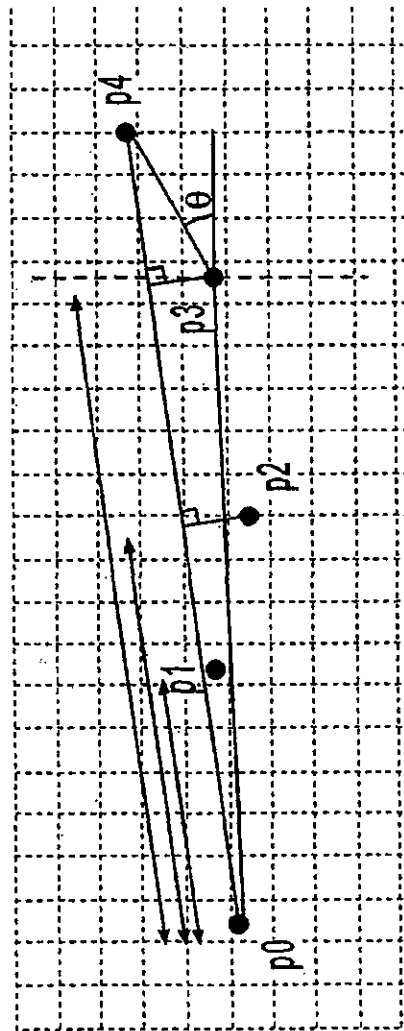


*Fig. 3c*

*Fig. 4a*

*Fig. 4b*

7/23

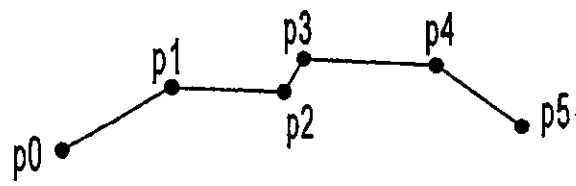


*Fig. 5a*

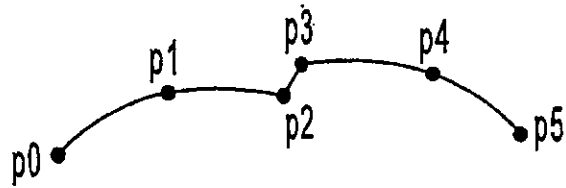


*Fig. 5b*

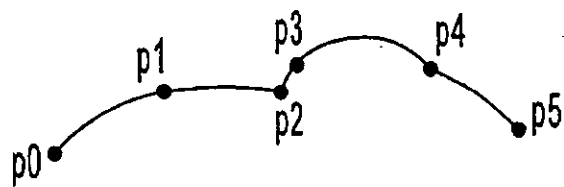


*Fig. 5c*

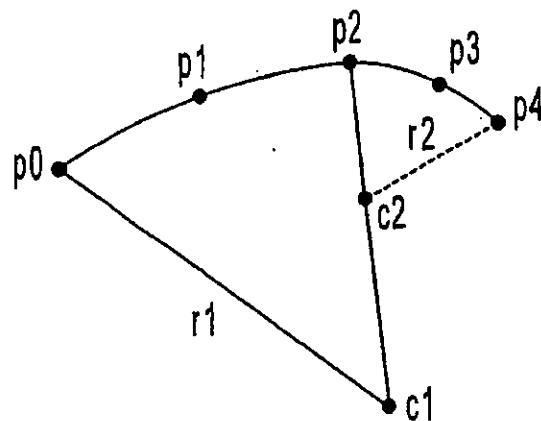


*Fig. 5d*

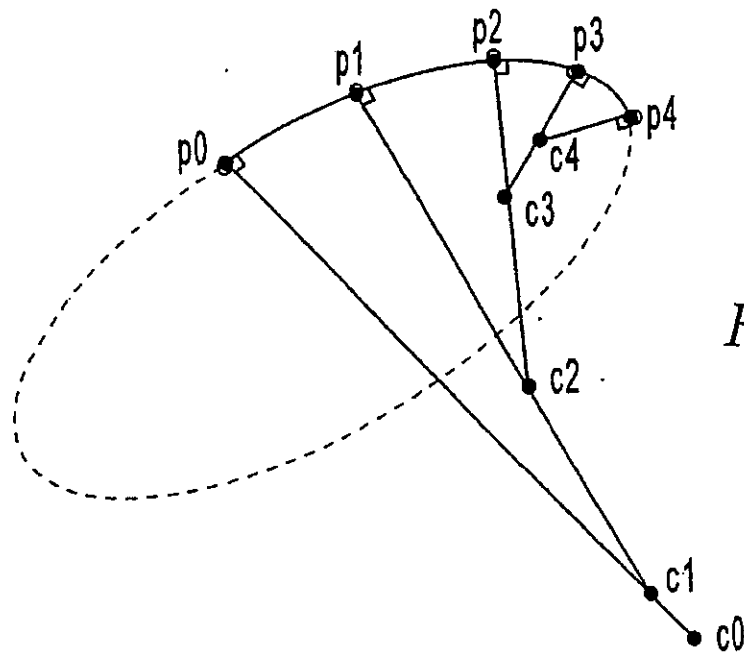
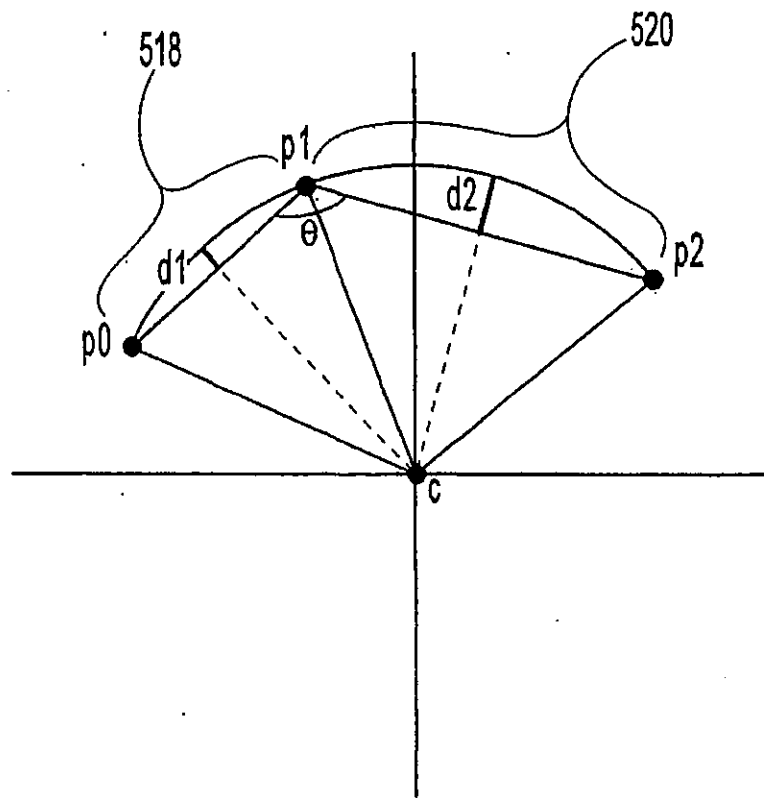


*Fig. 5e*

*Fig. 6*

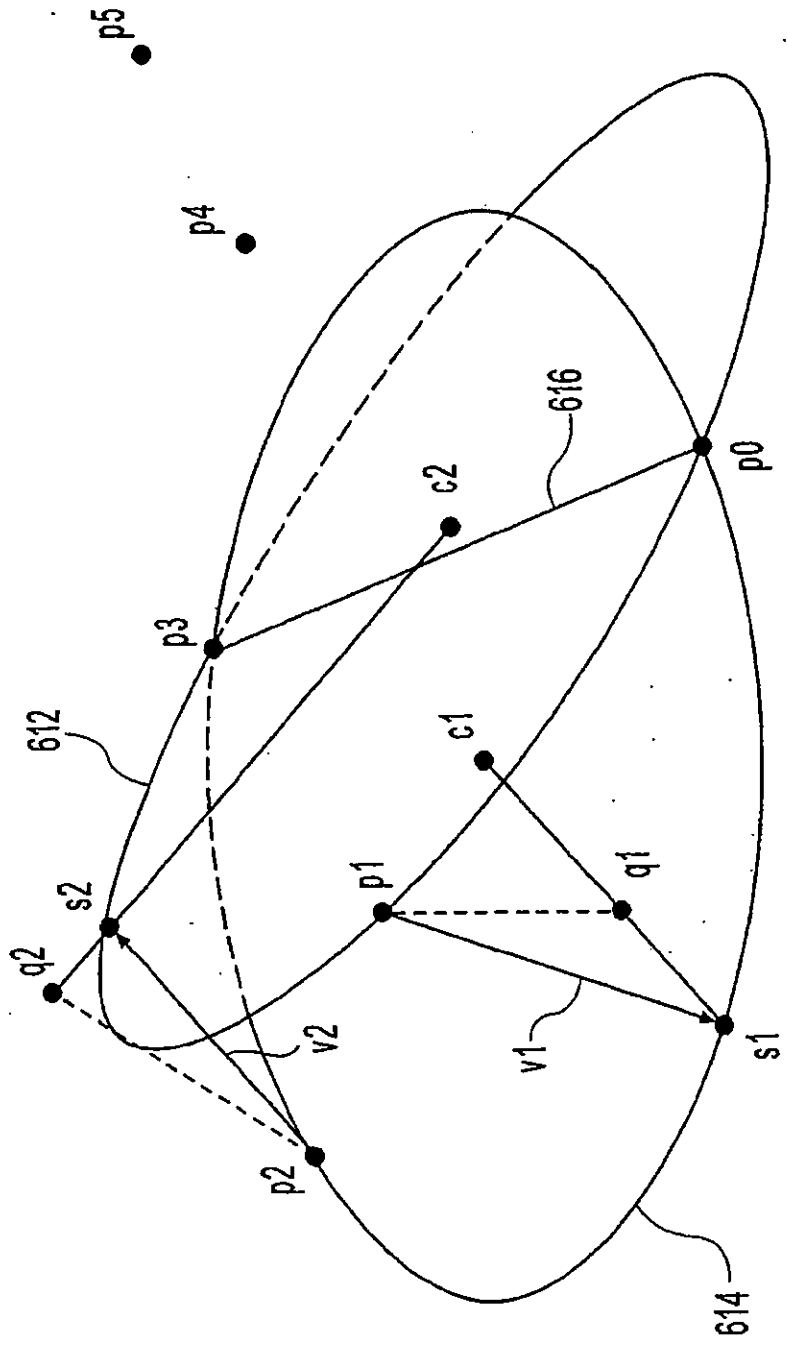
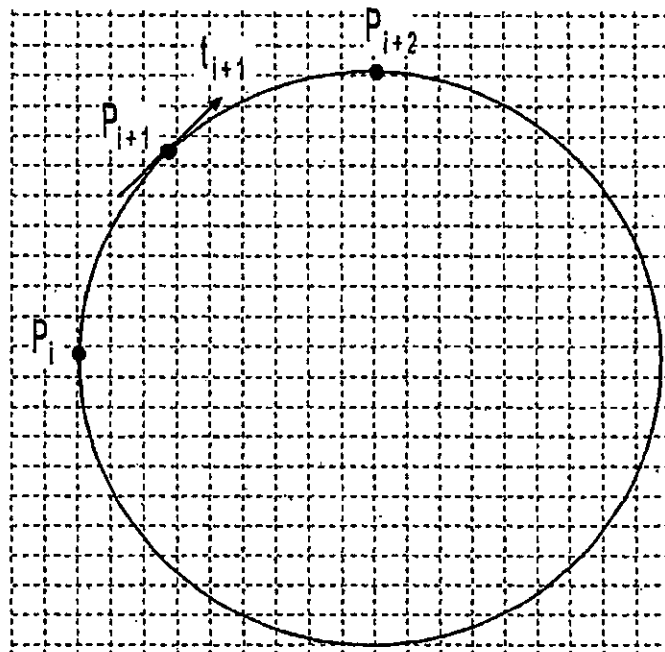


Fig. 7

*Fig. 8*

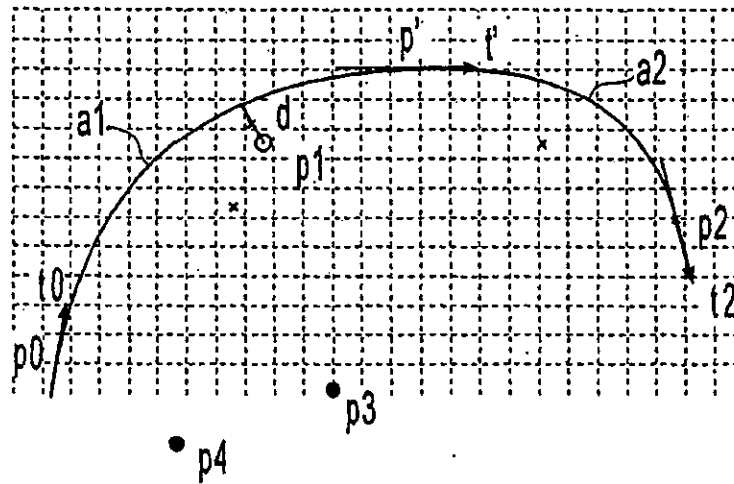


Fig. 9

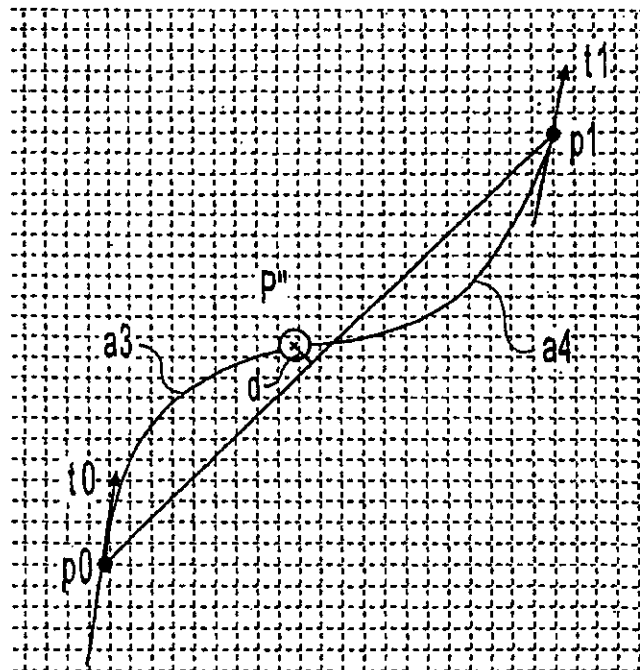


Fig. 10

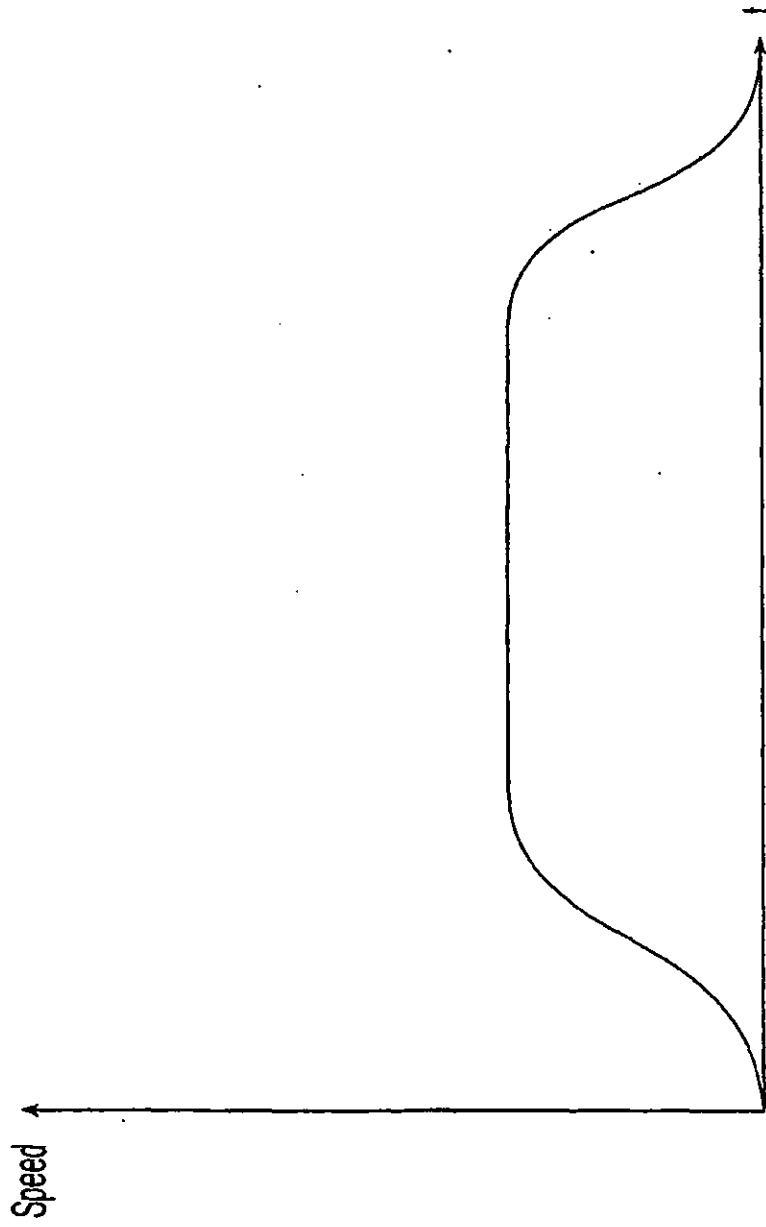
*Fig. 11*

Fig. 12a

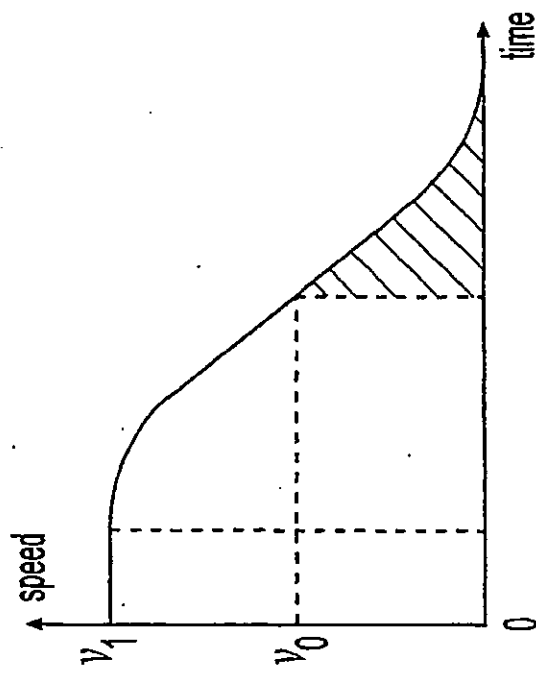
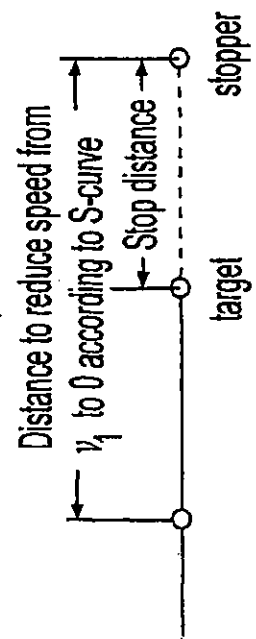


Fig. 12b



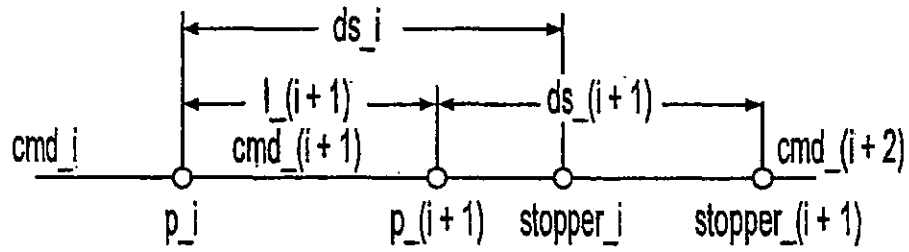


Fig. 13

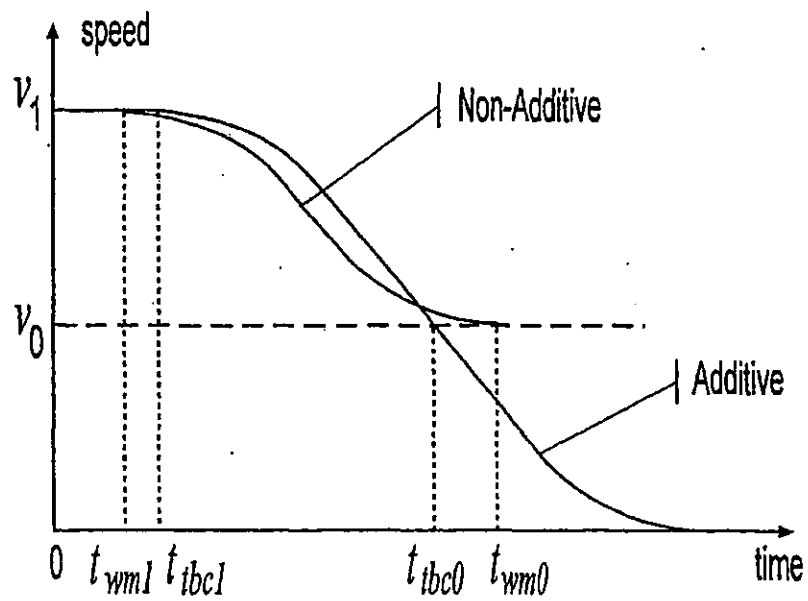
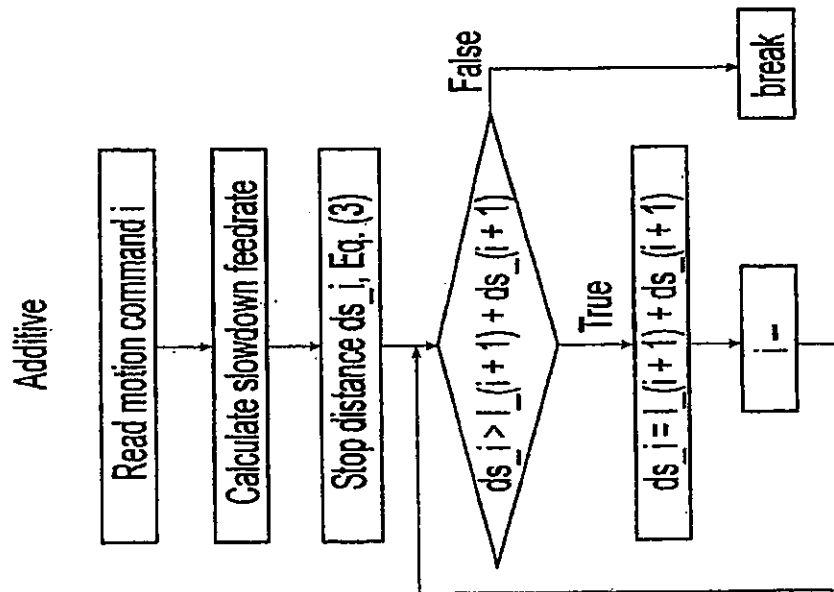


Fig. 14

*Fig. 15*

## Non - TBC Motion Control

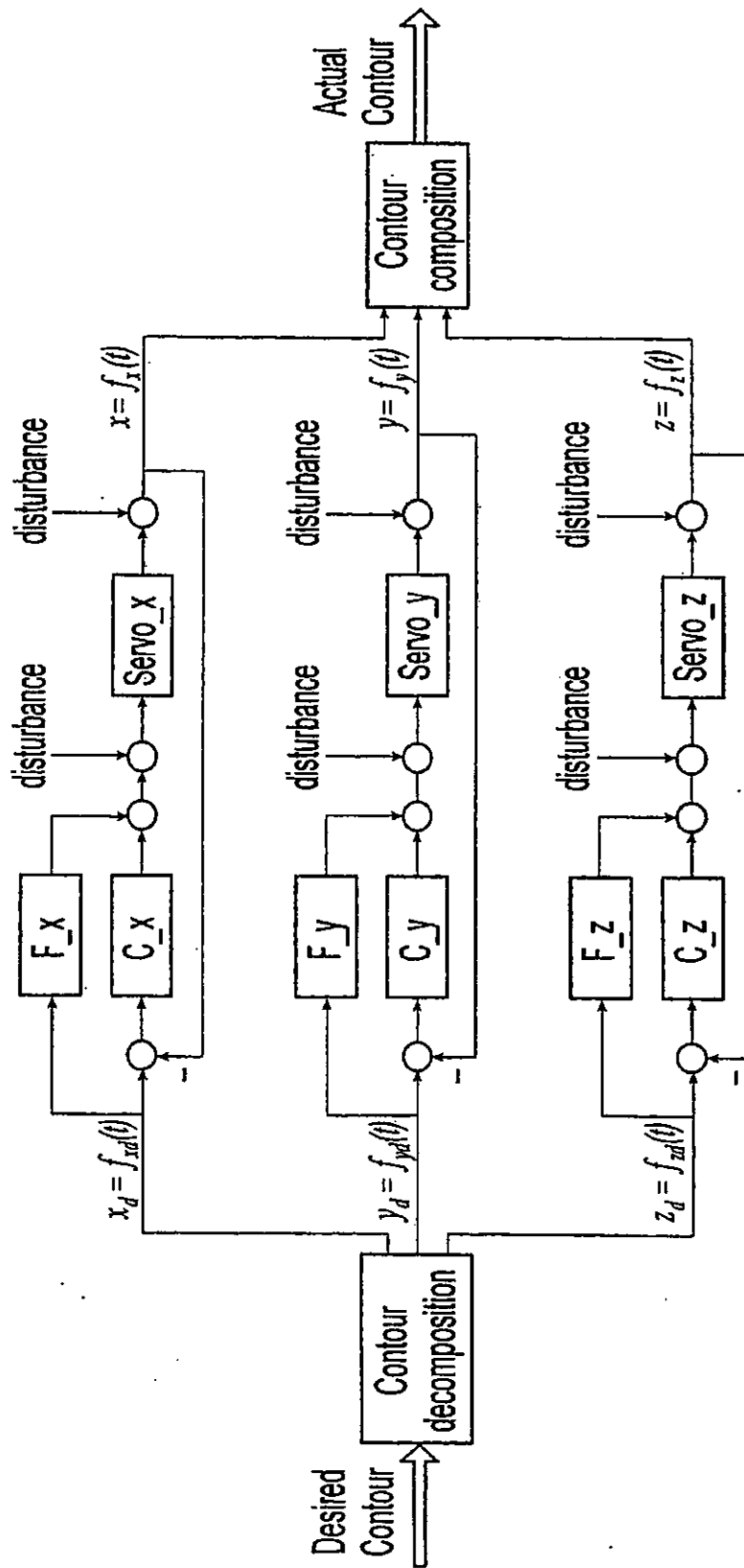


Fig. 16

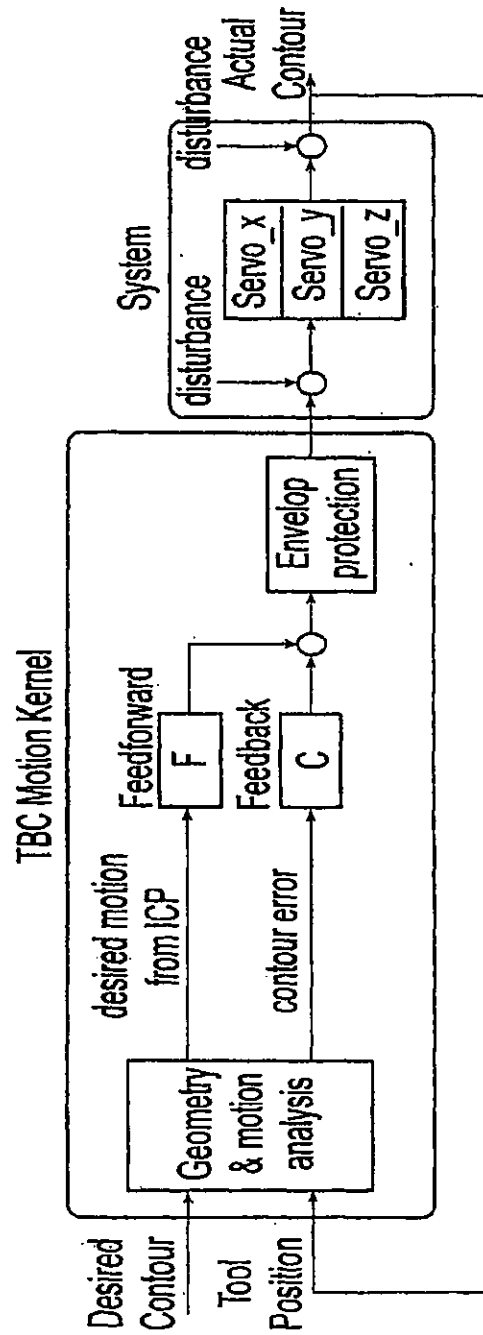
*Fig. 17*



Fig. 18

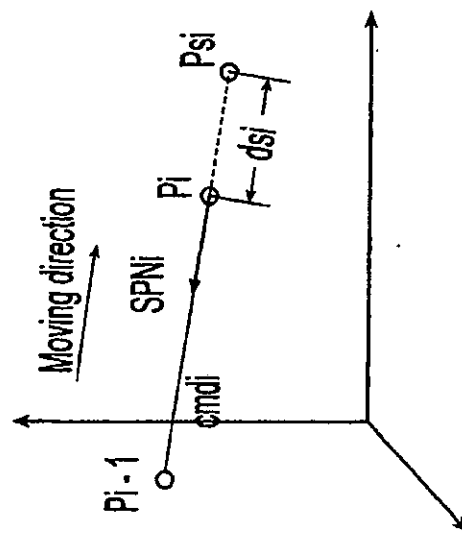
*Fig. 19*

Fig. 20

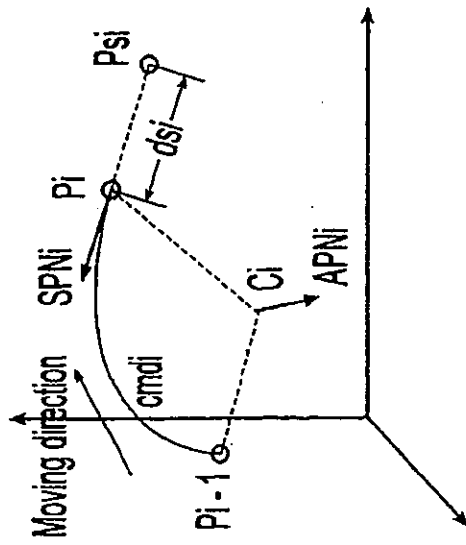
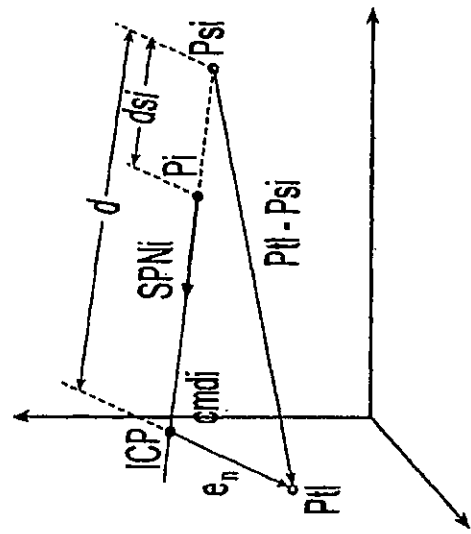


Fig. 21



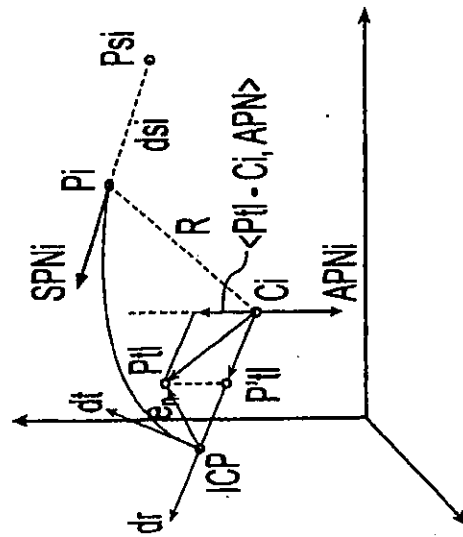


Fig. 22a

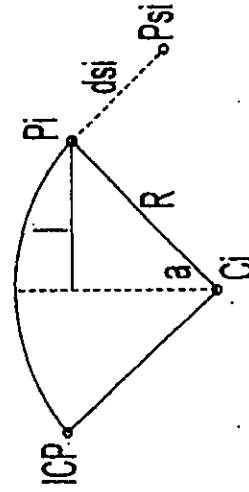
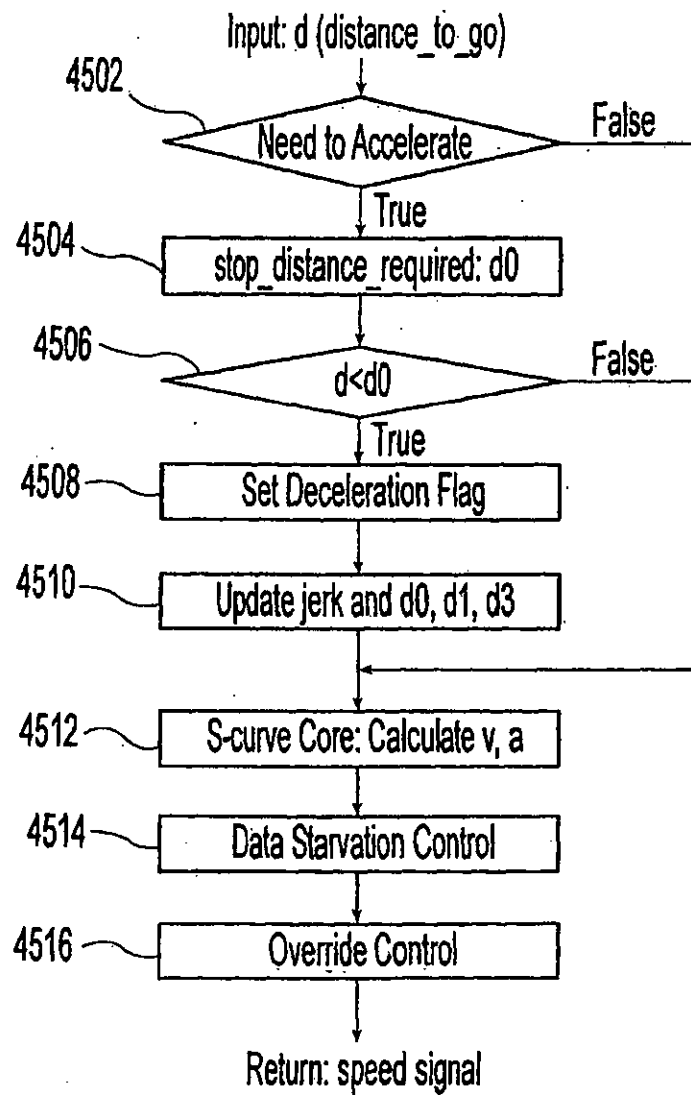


Fig. 22b

*Fig. 23*

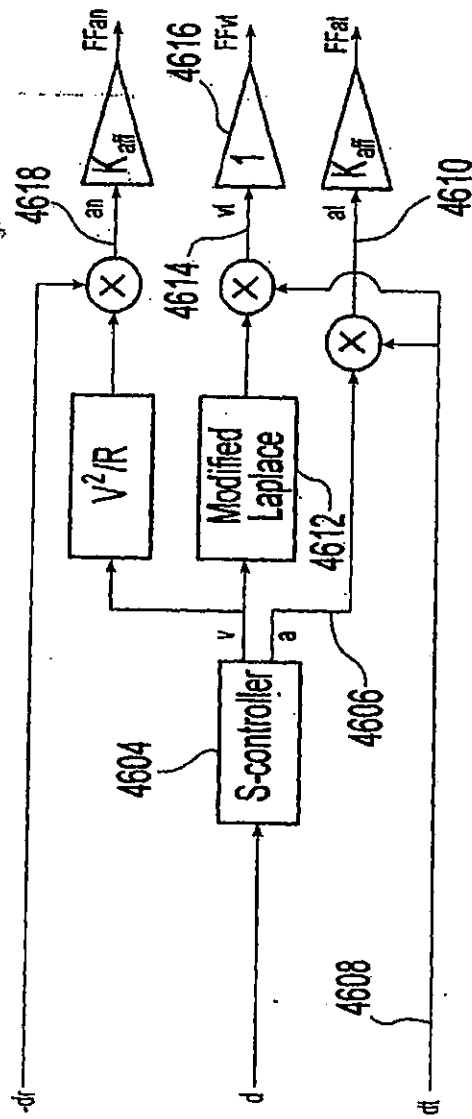


Fig. 24

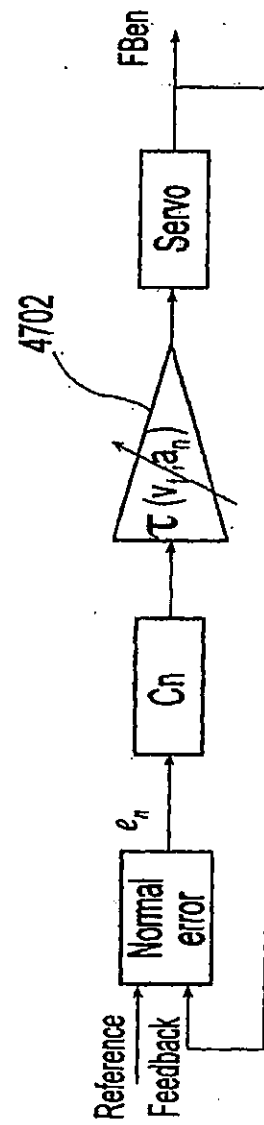


Fig. 25