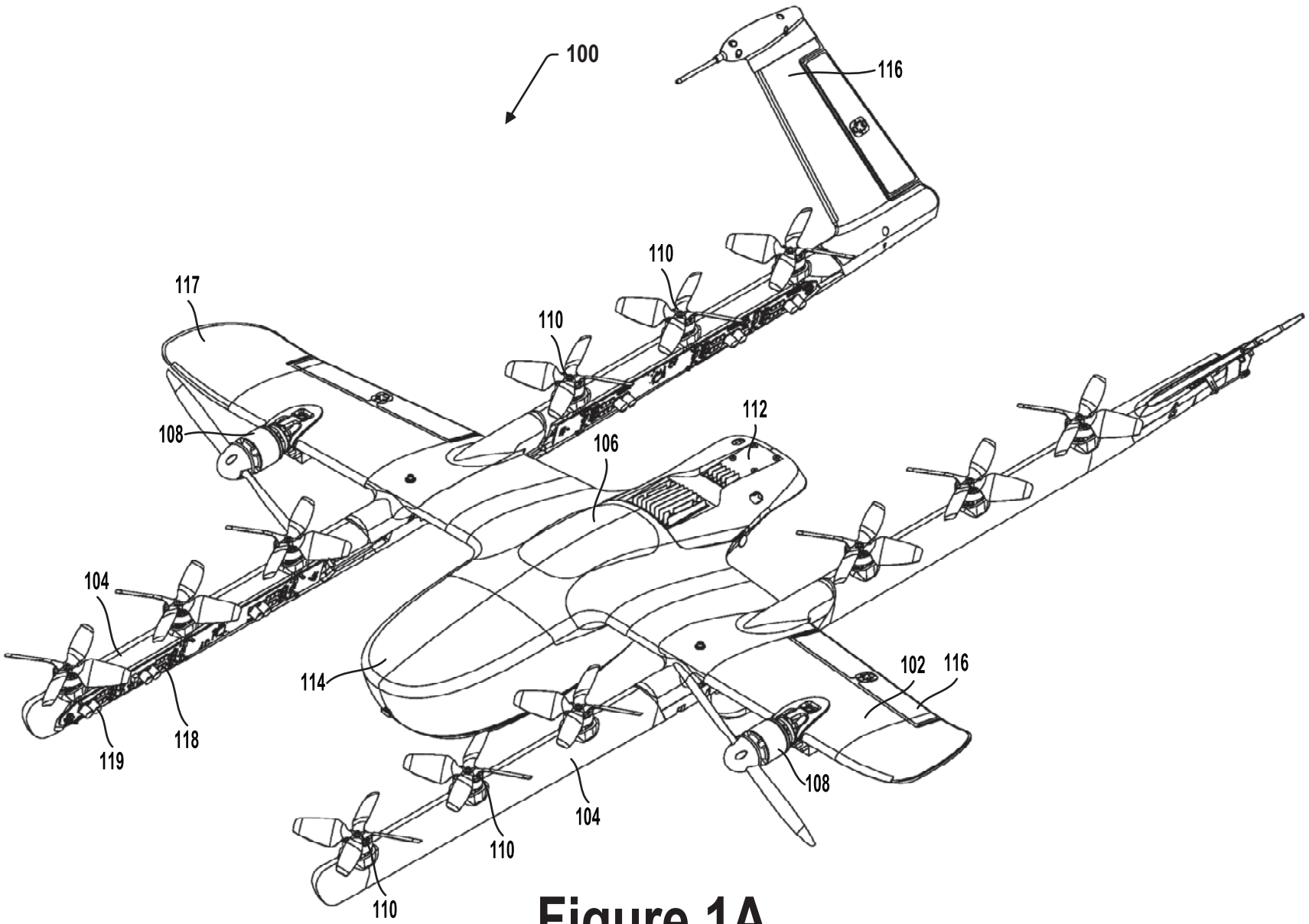

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Figure 1A

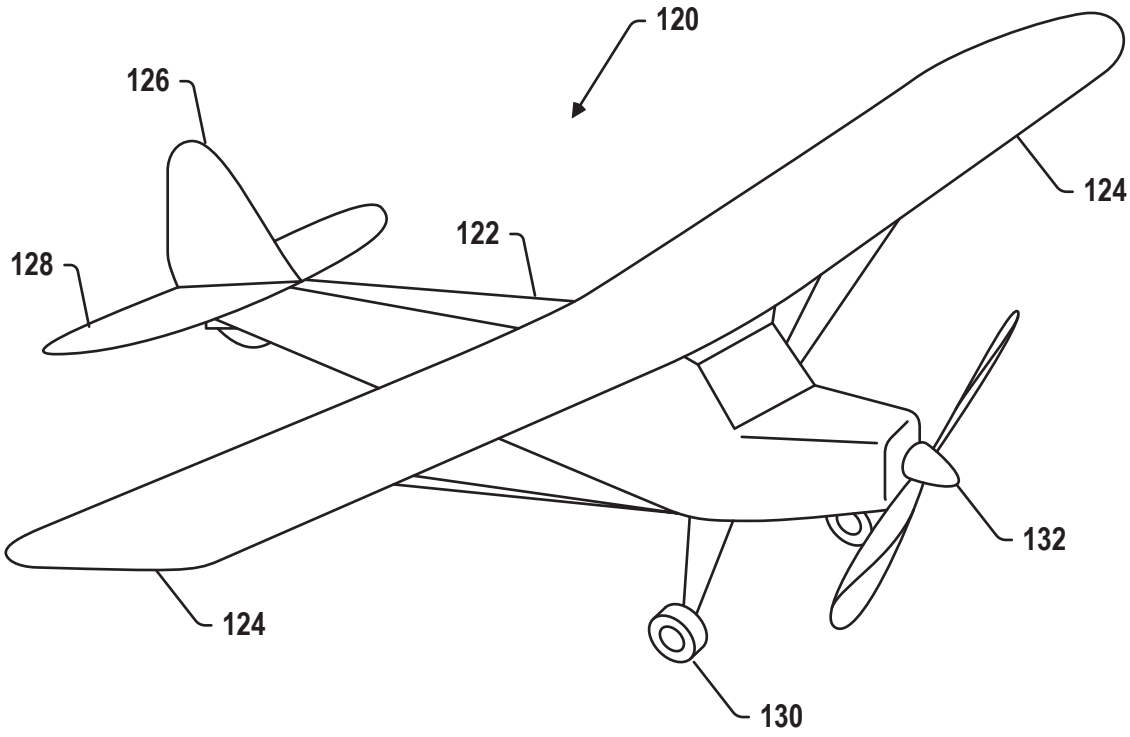


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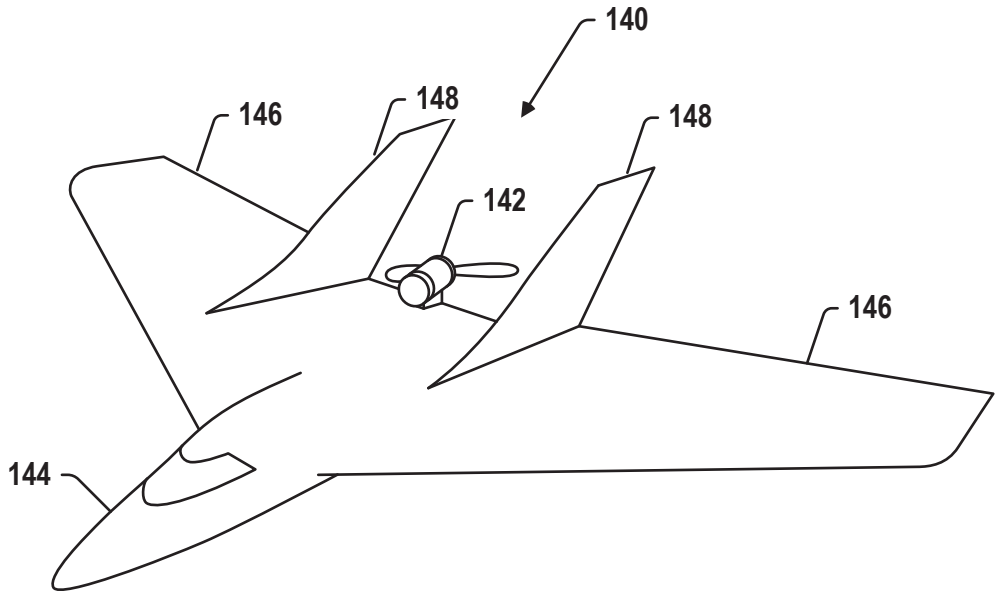


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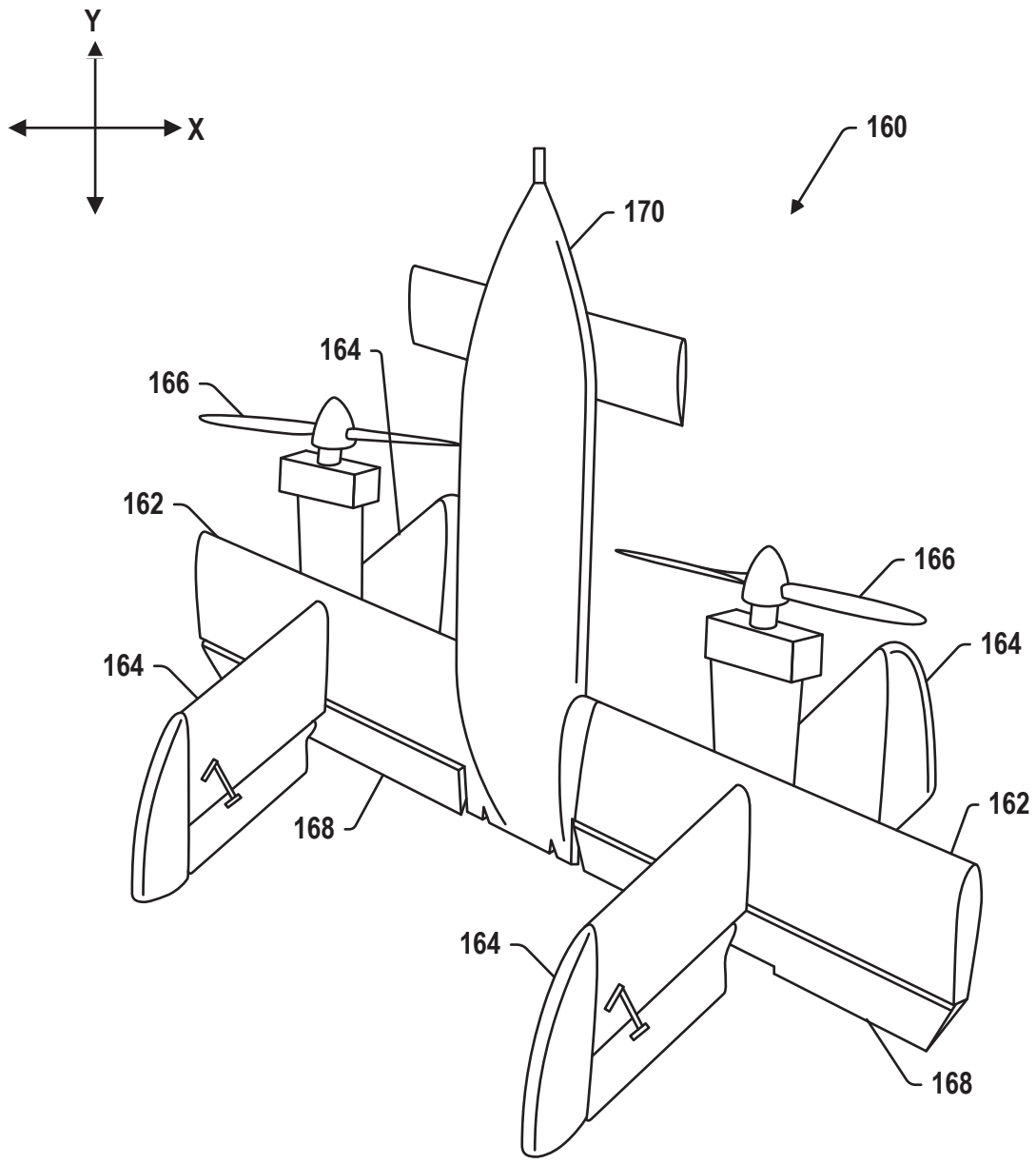


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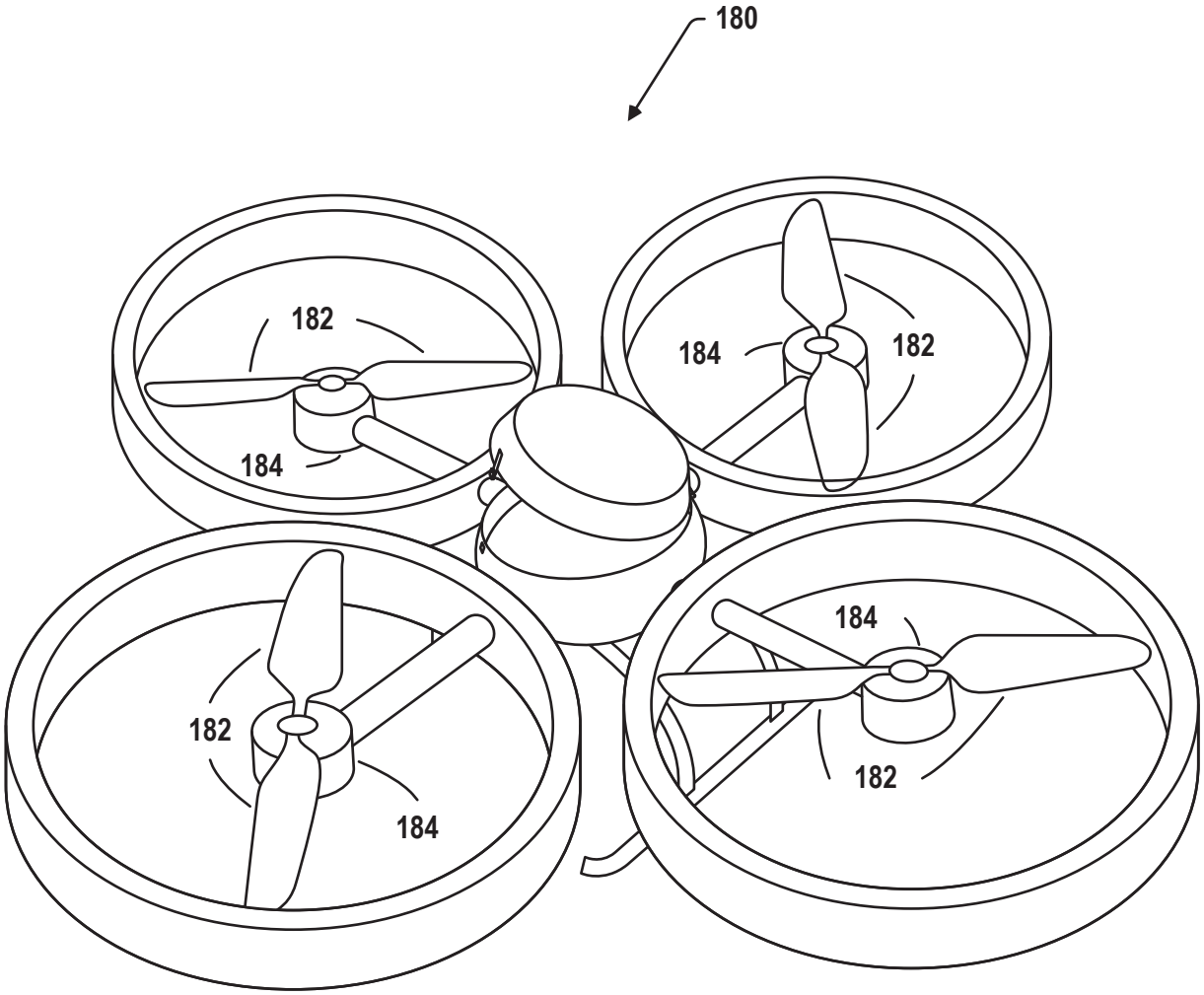


FIG. 1E

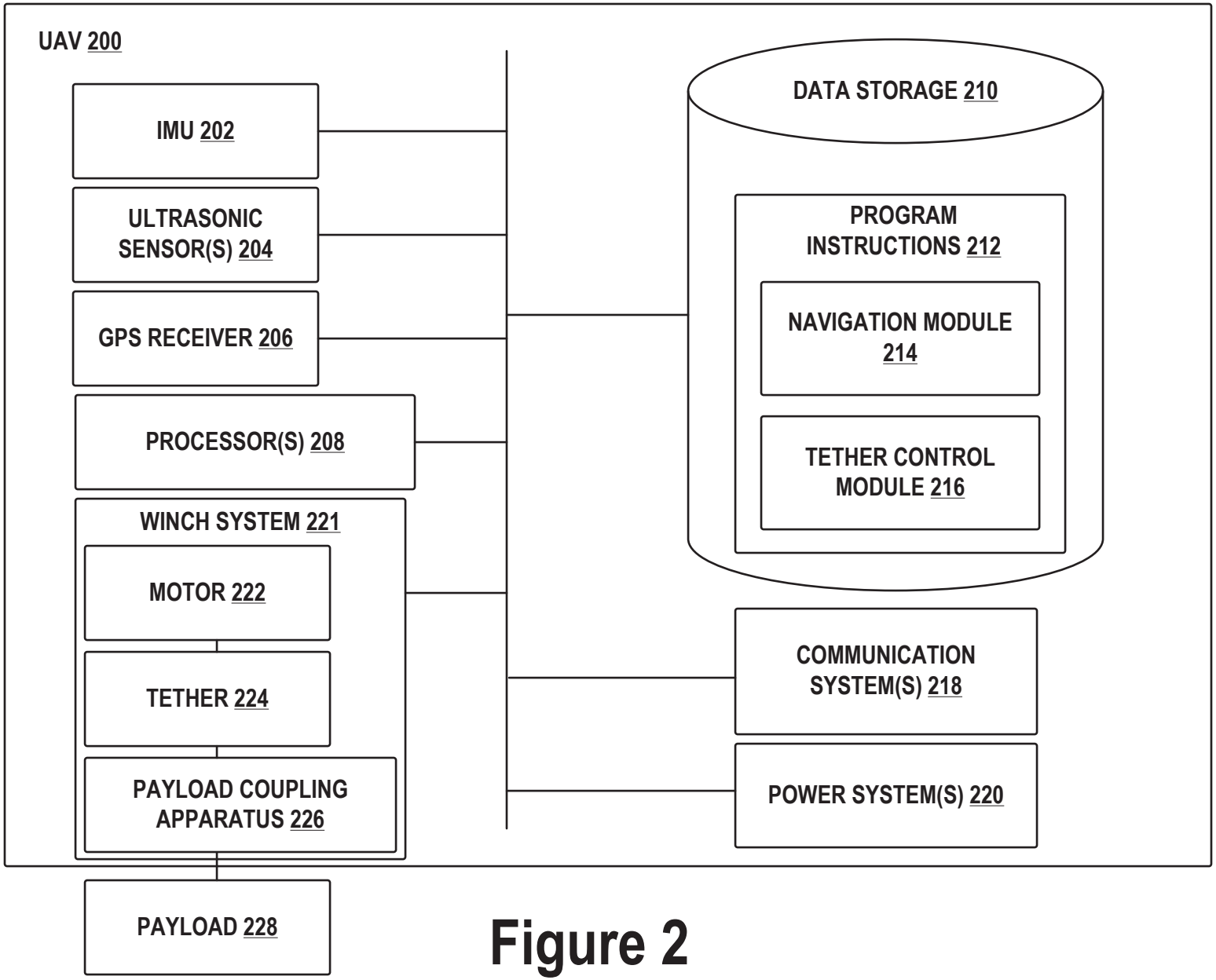

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PROCESSOR(S) 208
WINCH SYSTEM 221
MOTOR 222
TETHER 224
PAYLOAD COUPLING APPARATUS 226
PAYLOAD 228
DATA STORAGE 210
PROGRAM INSTRUCTIONS 212
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TETHER CONTROL MODULE 216
COMMUNICATION SYSTEM(S) 218
POWER SYSTEM(S) 220

Figure 2

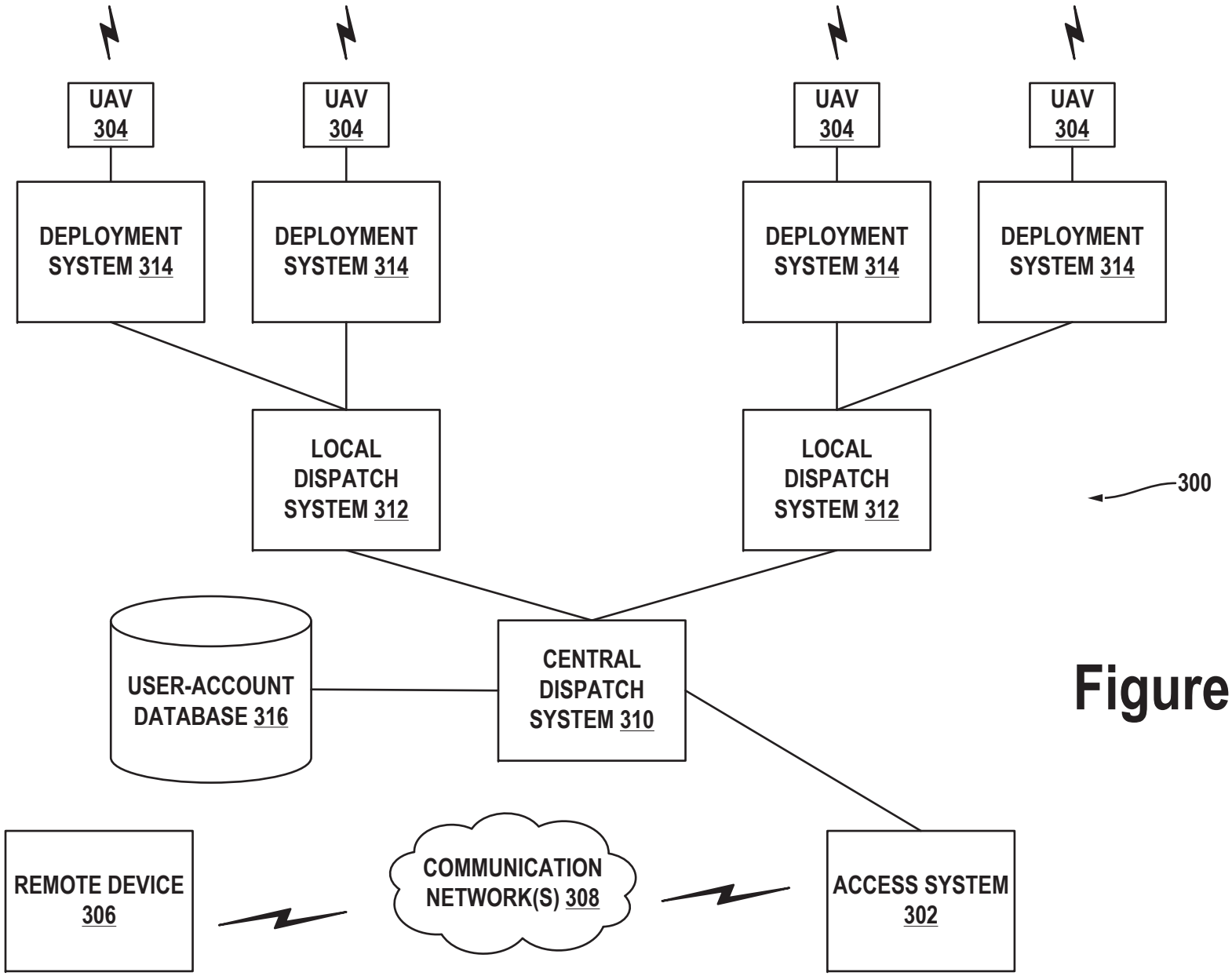

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UAV 304
UAV 304
UAV 304
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DEPLOYMENT SYSTEM 314
DEPLOYMENT SYSTEM 314
DEPLOYMENT SYSTEM 314
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LOCAL DISPATCH SYSTEM 312
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USER-ACCOUNT DATABASE 316
CENTRAL DISPATCH SYSTEM 310
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Figure 3

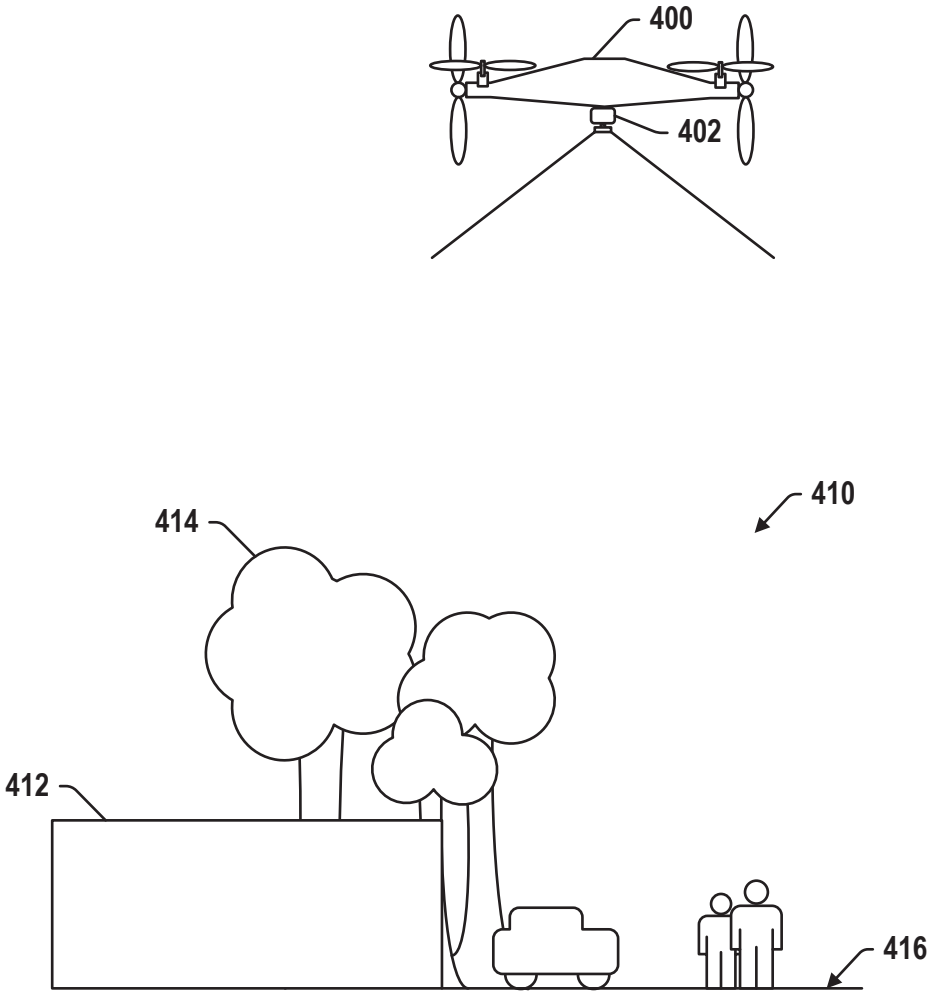


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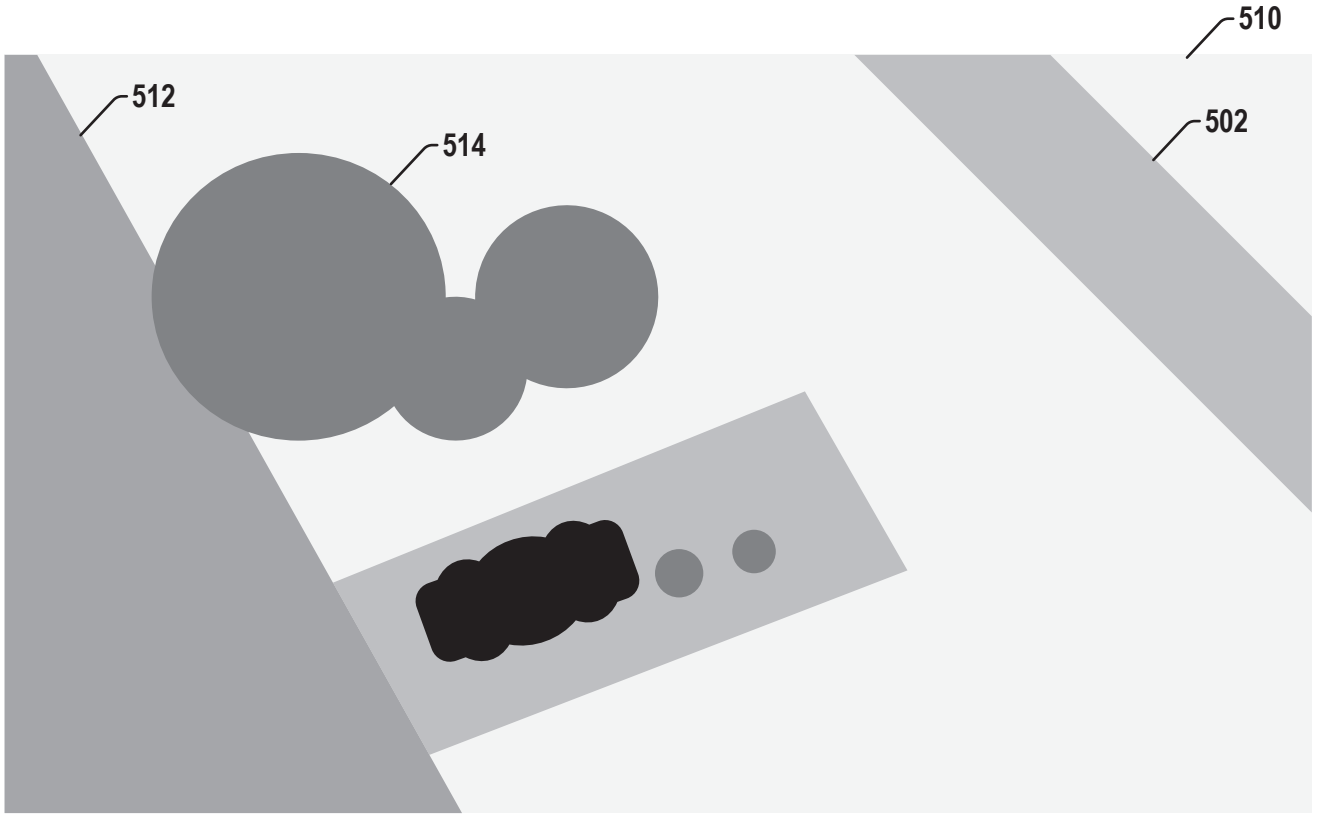


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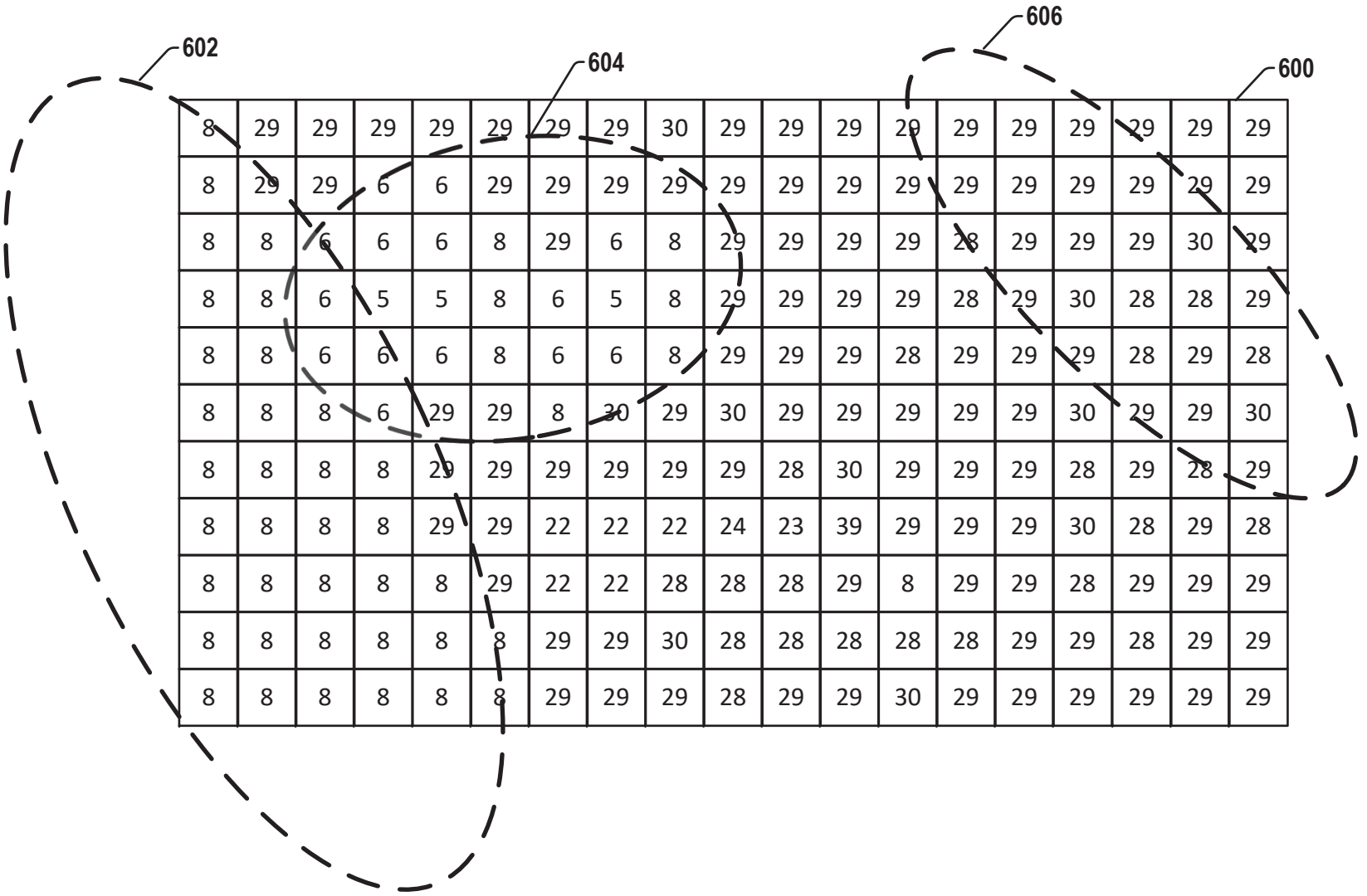

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Figure 6

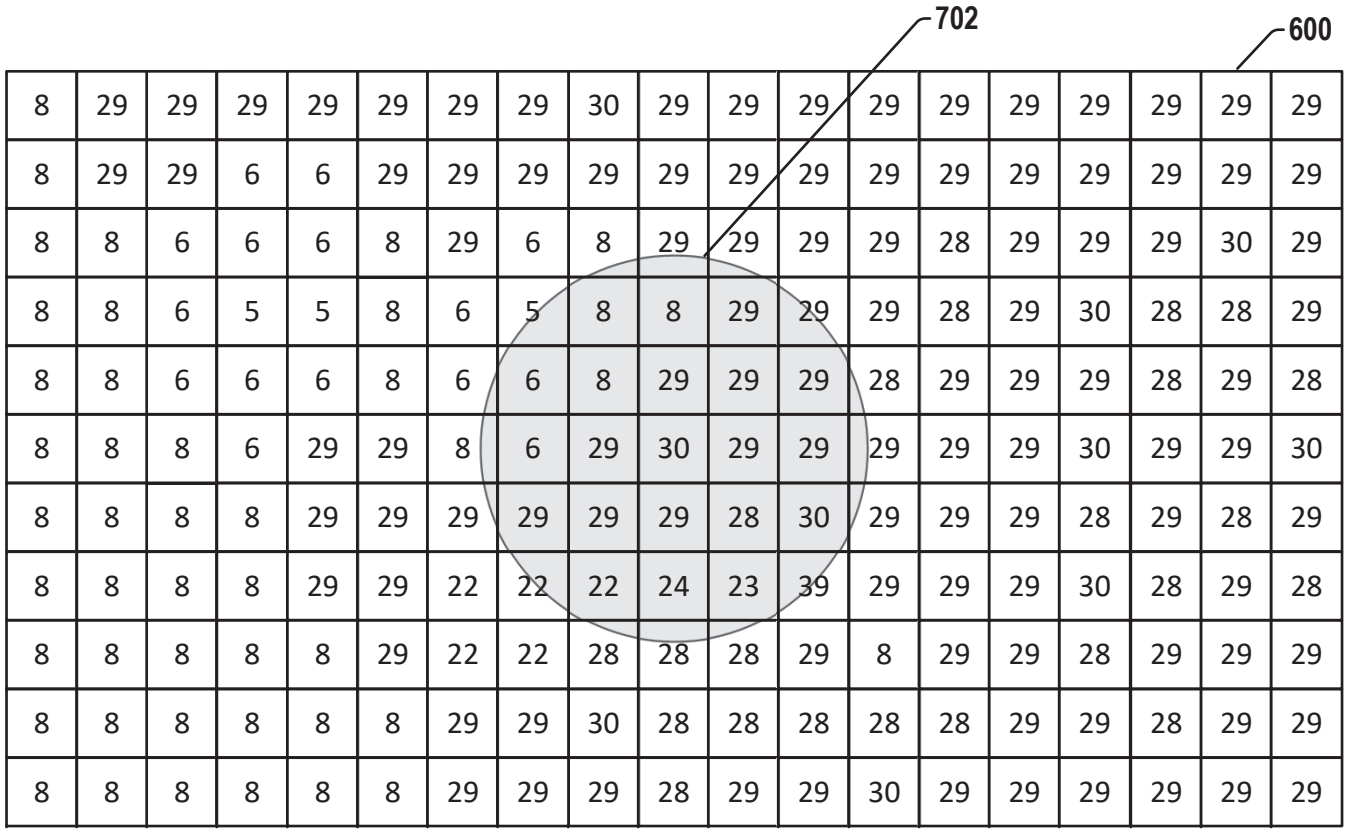

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Figure 7

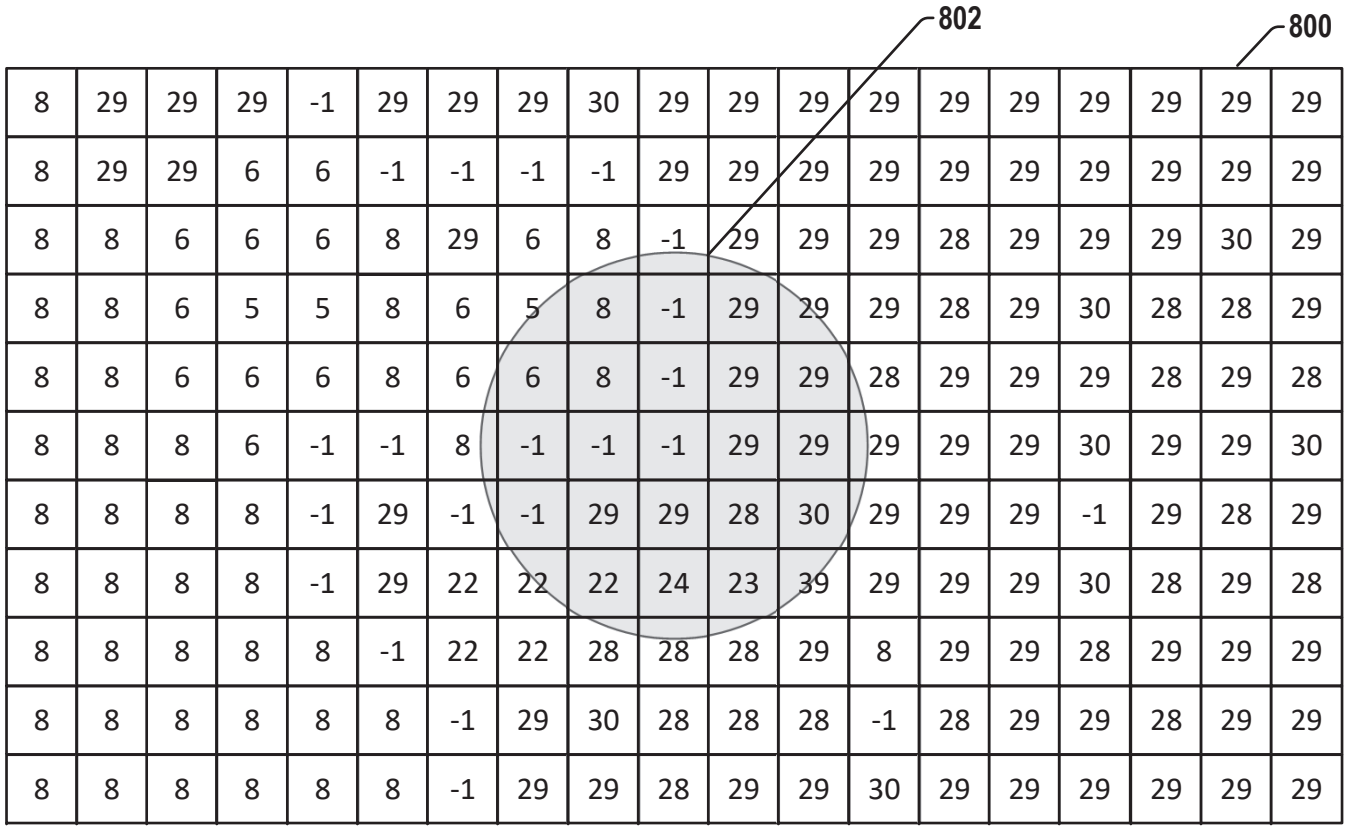

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Figure 8

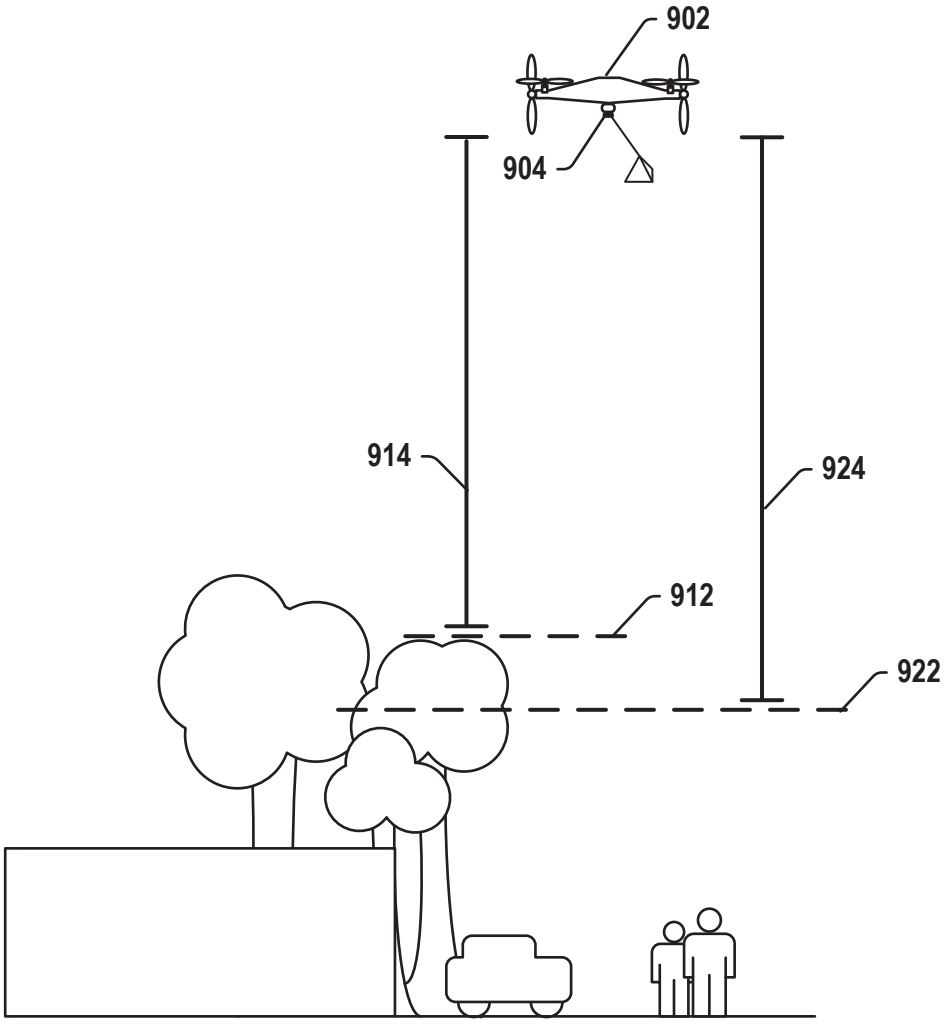


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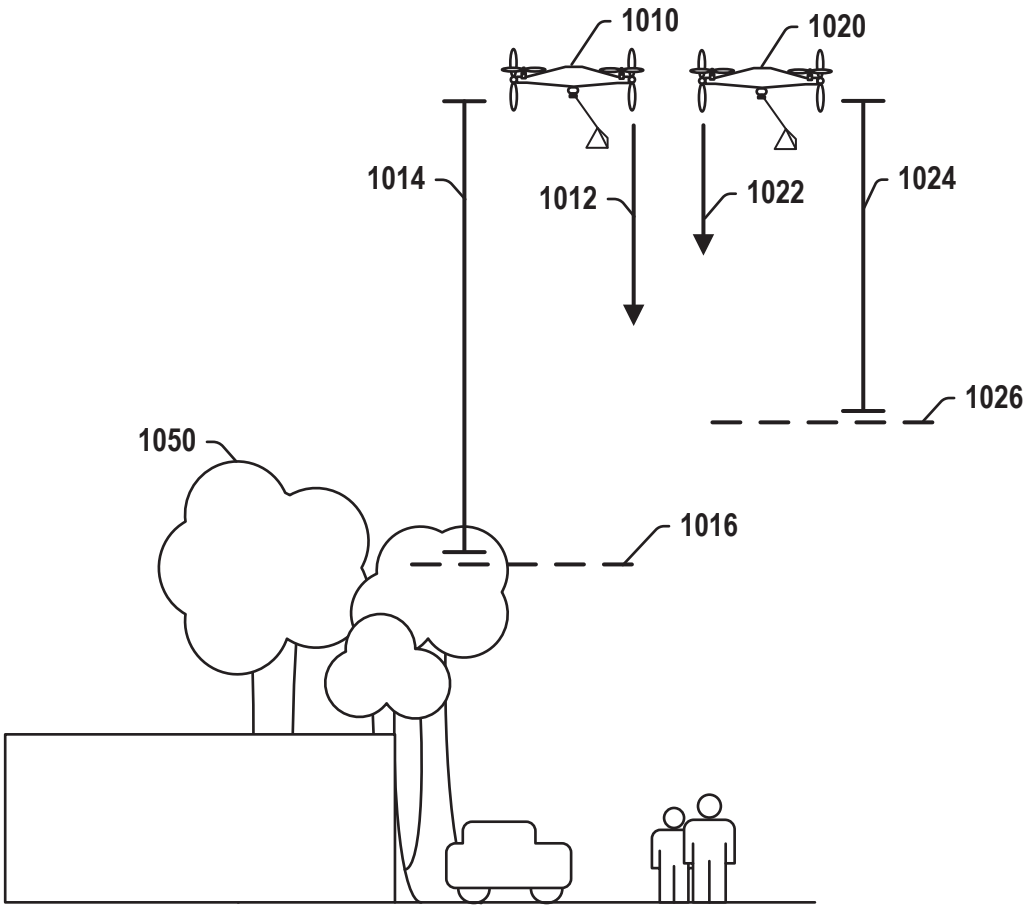


Figure 10

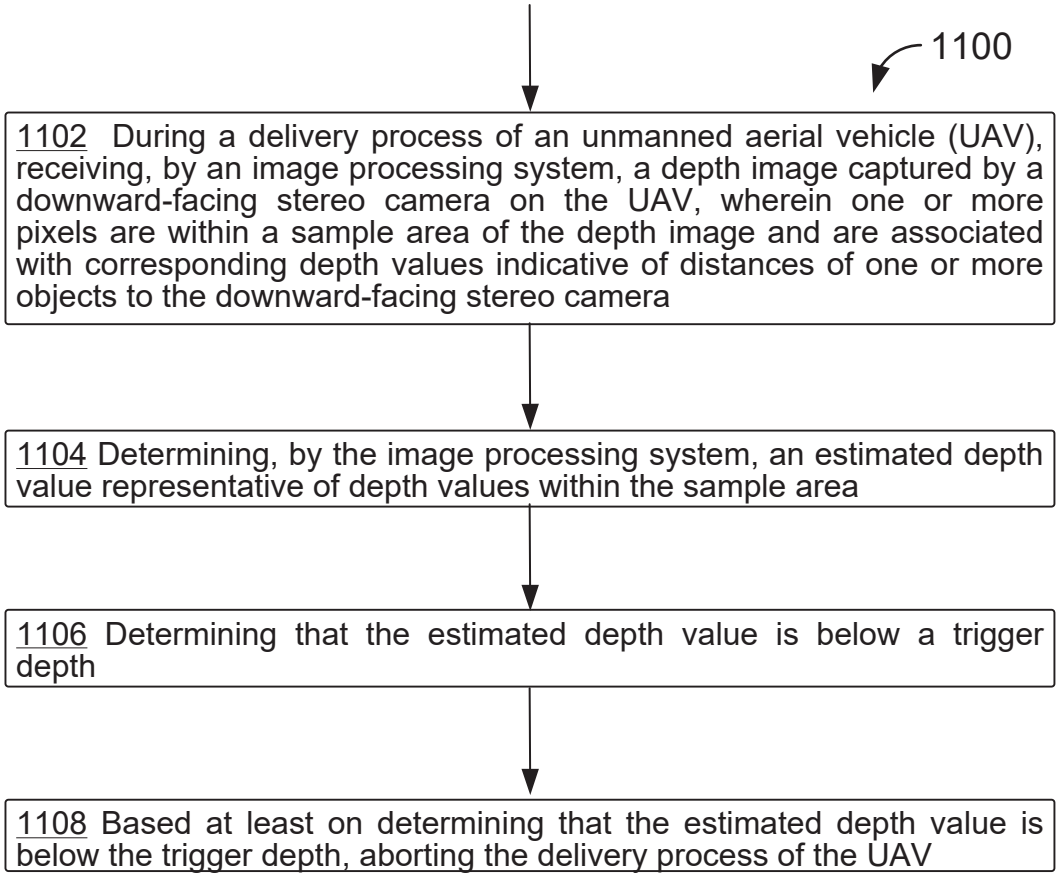

1100
1102 During a delivery process of an unmanned aerial vehicle (UAV), receiving, by an image processing system, a depth image captured by a downward-facing stereo camera on the UAV, wherein one or more pixels are within a sample area of the depth image and are associated with corresponding depth values indicative of distances of one or more objects to the downward-facing stereo camera
1104 Determining, by the image processing system, an estimated depth value representative of depth values within the sample area
1106 Determining that the estimated depth value is below a trigger depth
1108 Based at least on determining that the estimated depth value is below the trigger depth, aborting the delivery process of the UAV

Figure 11