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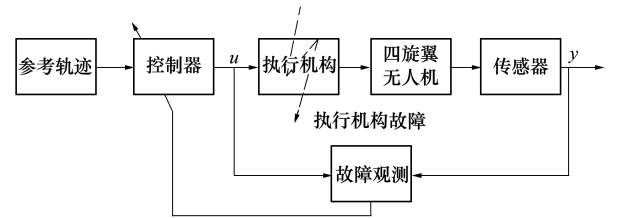
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$$\begin{cases} \hat{f}_{dz} = k_{z\beta} \% \dot{\theta}_q - \dot{z}_f \circ \\ \hat{v}_z = u_z \% \dot{\theta} \varphi \dot{\psi} \theta \circ - g - \hat{f}_{dz} - k_{z0} \% \dot{\theta}_q - \dot{z}_f \circ \\ \hat{f}_{d\varphi} = k_{\varphi\beta} \% \dot{\theta}_q - p \circ \\ \hat{p} = \frac{J_y - J_z}{J_x} q r + u_\varphi l + \frac{J_r q \Omega}{J_x} - \hat{f}_{d\varphi} - k_{\varphi 0} \% \dot{\theta}_q - p \circ \end{cases}$$

$$\begin{cases} \hat{f}_{d\theta} = k_{\theta 0} \dot{\varphi}_0 - q_0 \\ \hat{q} = \frac{J_z - J_x}{J_y} pr + u_{\theta} l - \frac{J_r p \Omega}{J_y} - \hat{f}_{d\theta} - k_{\theta 0} \dot{\varphi}_0 - q_0 \\ \hat{f}_{d\psi} = k_{\psi 0} \dot{\varphi}_0 - r_0 \\ \hat{r} = \frac{J_x - J_y}{J_z} pq + cu_{\psi} - \hat{f}_{d\psi} - k_{\psi 0} \dot{\varphi}_0 - r_0 \end{cases} \quad \% \times 0$$

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$$\begin{cases} \dot{s}_z = \lambda_z \dot{\varphi}_0 - z_0 + \alpha \dot{\varphi}_0 - \alpha_0 \dot{\varphi}_0 \dot{\varphi} \dot{\varphi} \theta_0 - g - f_{dz} \circ \circ + k_z \dot{\varphi}_0 - z_0 \\ s_{\varphi} = \ddot{\varphi}_d - \left(\frac{J_y - J_z}{J_x} qr + u_{\varphi} l + \frac{J_r q \Omega}{J_x} - f_{d\varphi} \right) + \alpha \lambda_{\varphi} \dot{\varphi}_d - \dot{\varphi}_0 + k_{\varphi} \dot{\varphi}_d - \varphi_0 \\ s_{\theta} = \ddot{\theta}_d - \left(\frac{J_z - J_x}{J_y} pr + u_{\theta} l - \frac{J_r p \Omega}{J_y} - f_{d\theta} \right) + \alpha \lambda_{\theta} \dot{\theta}_d - \dot{\theta}_0 + k_{\theta} \dot{\theta}_d - \theta_0 \\ s_{\psi} = \ddot{\psi}_d - \left(\frac{J_x - J_y}{J_z} pq + cu_{\psi} - f_{d\psi} \right) + \alpha \lambda_{\psi} \dot{\psi}_d - \dot{\psi}_0 + k_{\psi} \dot{\psi}_d - \psi_0 \end{cases} \quad \% \circ$$

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$$\begin{cases} u_z = \frac{\beta}{\dot{\varphi} \theta \dot{\varphi} \varphi} \ddot{z}_d + g + \lambda_z \dot{\varphi}_0 - z_0 + \alpha k_z e_z + \hat{f}_{dz} + k_{pz} U_{W\varphi} \circ \circ \\ u_{\varphi} = \frac{\beta}{l} \dot{\varphi}_d - \frac{J_y - J_z}{J_x} qr + \frac{J_r q \Omega}{J_x} \circ + \lambda_{\varphi} \dot{\varphi}_d - \dot{\varphi}_0 + \alpha k_{\varphi} \dot{\varphi}_d - \varphi_0 + \hat{f}_{d\varphi} + k_{p\varphi} k_i \dot{\varphi}_0 \circ \circ \\ u_{\theta} = \frac{\beta}{l} \dot{\theta}_d - \frac{J_z - J_x}{J_y} pr - \frac{J_r p \Omega}{J_y} \circ + \lambda_{\theta} \dot{\theta}_d - \dot{\theta}_0 + \alpha k_{\theta} \dot{\theta}_d - \theta_0 + \hat{f}_{d\theta} + k_{p\theta} k_i \dot{\theta}_0 \circ \circ \\ u_{\psi} = \frac{\beta}{c} \dot{\psi}_d - \frac{J_x - J_y}{J_z} pq \circ + \lambda_{\psi} \dot{\psi}_d - \dot{\psi}_0 + \alpha k_{\psi} \dot{\psi}_d - \psi_0 + \hat{f}_{d\psi} + k_{p\psi} k_i \dot{\psi}_0 \circ \circ \end{cases} \quad \% \circ$$

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$$\begin{cases} u_x = \frac{\beta}{u_z} \ddot{x}_d + \lambda_x \dot{\varphi}_0 - \dot{x}_0 + k_x e_x + k_{px} U_{W\varphi} \circ \circ \\ u_y = \frac{\beta}{u_z} \ddot{y}_d + \lambda_y \dot{\varphi}_0 - \dot{y}_0 + k_y e_y + k_{py} U_{W\varphi} \circ \circ \end{cases} \quad \% \circ$$

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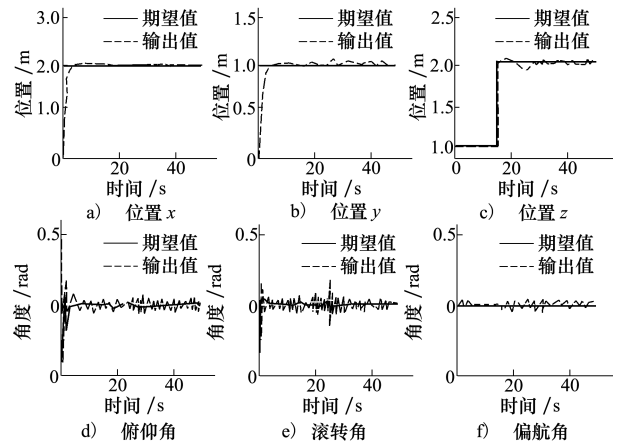
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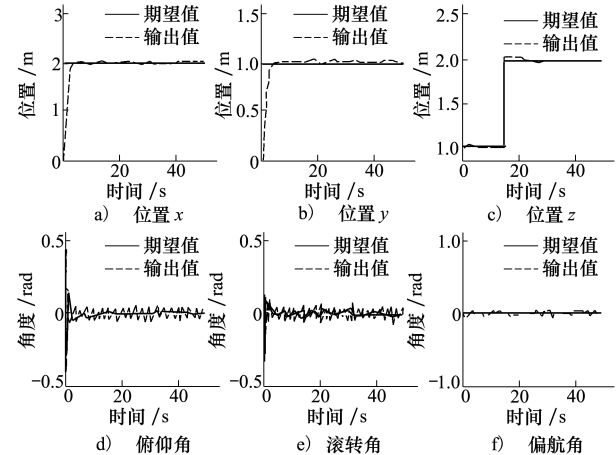
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| æJFN Ô c | $k_x \%B$ | $k_y \%B$ | $k_z \%B!$ | $k_\varphi \%B!$ | $k_\theta \%B!$ | $k_\psi \%B!$ |
| i • | $k_{px} \%d !B$ | $k_{py} \%d !B$ | $k_{pz} \%d !B$ | $k_{p\varphi} \%B!$ | $k_{p\theta} \%B!$ | $k_{p\psi} \%0$ |
| | $\sigma_x \%d !B$ | $\sigma_y \%d !B$ | $\sigma_z \%d !!B$ | $\sigma_\varphi \%d !B$ | $\sigma_\theta \%d !B$ | $\sigma_\psi \%d !B$ |
| >i"x • | | | $k_{z0} \%B!$ | $k_{\varphi0} \%0!$ | $k_{\theta0} \%0!$ | $k_{\psi0} \%0!$ |
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