| **Page** | **Section** | **Line** | **Type** | **Comment/ Rationale** | **Source of Comment (Name/Agency)** | **Suggested Disposition** | **Disposition**  **(Completed by Principal Editor)** |
| --- | --- | --- | --- | --- | --- | --- | --- |
| C-5 | C2 |  | e | For consistency in the document (cf. Table 3-3, or equation MBA= on page C-6) subscripts should be used for the quaternion elements and rotation axes indices in:  Q1 = sin(φ/2) \* e1  Q2 = sin(φ/2) \* e2  Q3 = sin(φ/2) \* e3  QC = cos(φ/2)  Subscripts should be omitted only for keywords. | R. Kahle / DLR/GSOC | Should read:  Q1 = sin(φ/2) \* e1  Q2 = sin(φ/2) \* e2  Q3 = sin(φ/2) \* e3  QC = cos(φ/2) |  |
| C-6 | C3 |  | e | Same comment / rationale as above. Concerning Euler angles  θ1, θ2, θ3 | R. Kahle / DLR/GSOC | Should read:  θ1, θ2, θ3 |  |
| C-7 | C5 |  | e | Same comment / rationale as above. Concerning inertia matrix elements IXX, … | R. Kahle / DLR/GSOC | Should read IXX, … |  |
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