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dynamics are then represented by a system of four first order differential equations:  $\dot{x} = v \cdot \cos(\psi + \beta)$ ,  $\dot{y} = v \cdot \sin(\psi + \beta)$ ,  $\dot{\psi} = v / r \sin \beta$ ,  $\dot{v} = a$ , (2) with  $x$  and  $y$  the coordinates of the COM with respect to an inertial frame  $(O, X, Y)$ ,  $v$  the instantaneous

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