

ImpulsiveManeuverLOFFrame 4.1

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```
public class ImpulsiveManeuverLOFFrame {

    /**
     * @param args
     * @throws OrekitException
     */
    public static void main(String[] args) throws PatriusException {

        // Creating a mass model with a main part and with a tank
        final AssemblyBuilder builder = new AssemblyBuilder();

        // Main part (dry mass)
        final double dryMass = 1000.;
        builder.addMainPart("MAIN");
        builder.addProperty(new MassProperty(dryMass), "MAIN");

        // Tank part (ergols mass)
        final double ergolsMass = 100.;
        builder.addPart("TANK", "MAIN", Transform.IDENTITY);
        builder.addProperty(new MassProperty(ergolsMass), "TANK");

        final Assembly assembly = builder.returnAssembly();
        final MassProvider mm = new MassModel(assembly);

        // Event corresponding to the criteria to trigger the impulsive
maneuver
        // (when the S/C is at the apogee)
        final EventDetector event = new AnomalyDetector(PositionAngle.TRUE,
FastMath.PI);

        // Creation of the impulsive maneuver (20 m/s int the x vehicle
direction)
        final Vector3D deltaV = new Vector3D(20., 0., 0.);
        final double isp = 300.;
// SPECIFIC
        final ImpulseManeuver imp = new ImpulseManeuver(event, deltaV, isp,
mm, "TANK", LOFType.TNW);
// SPECIFIC

        System.out.println("DV components: "+imp.getDeltaVSat());
        // The getFrame() method is returning "null" as a LOF frame is not
define as a frame.
        // Nevertheless, an attitude law will not be mandatory when
propagating the orbit.
```

```
        System.out.println("Maneuver frame: "+imp.getFrame());
    }
}
```

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