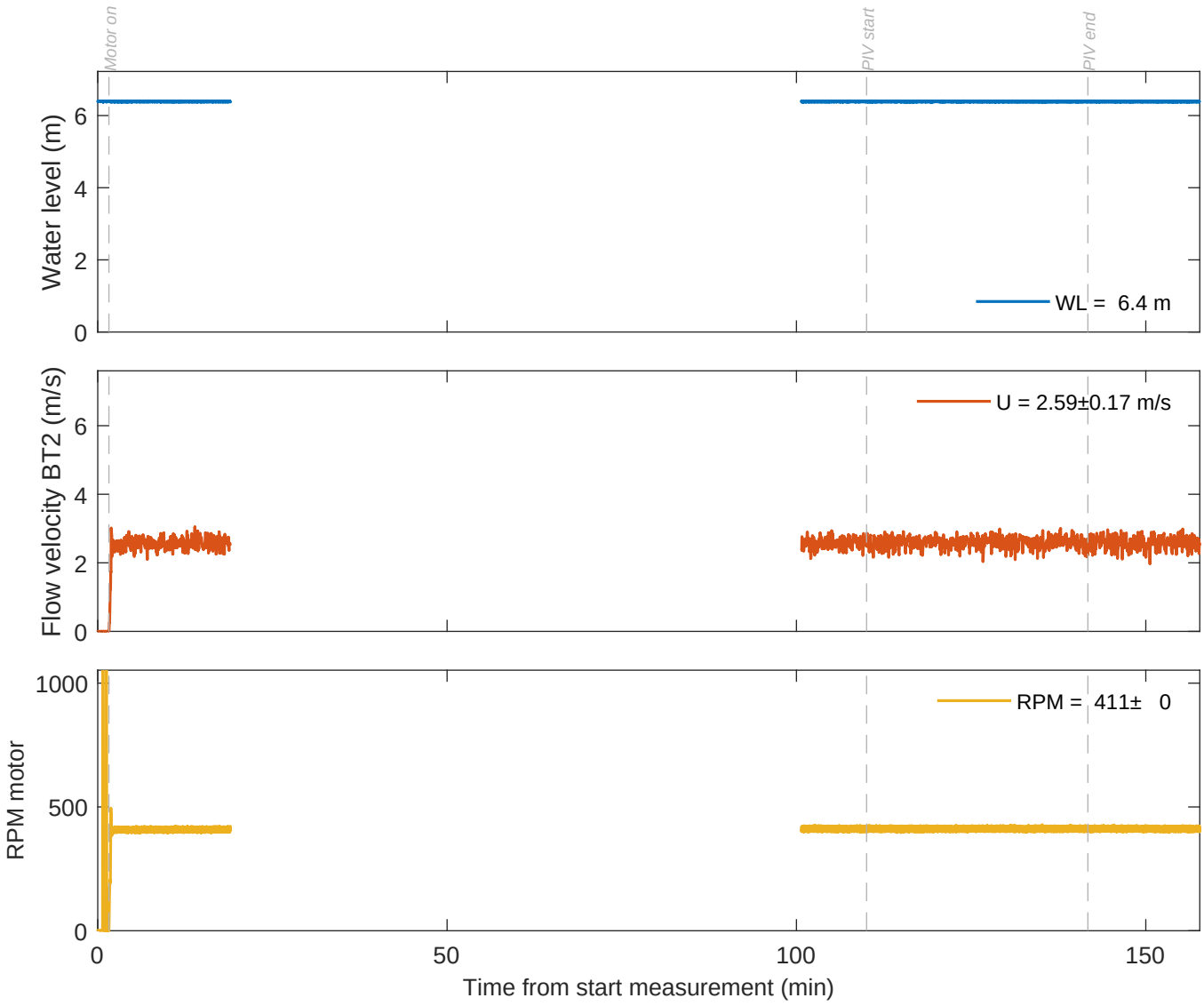
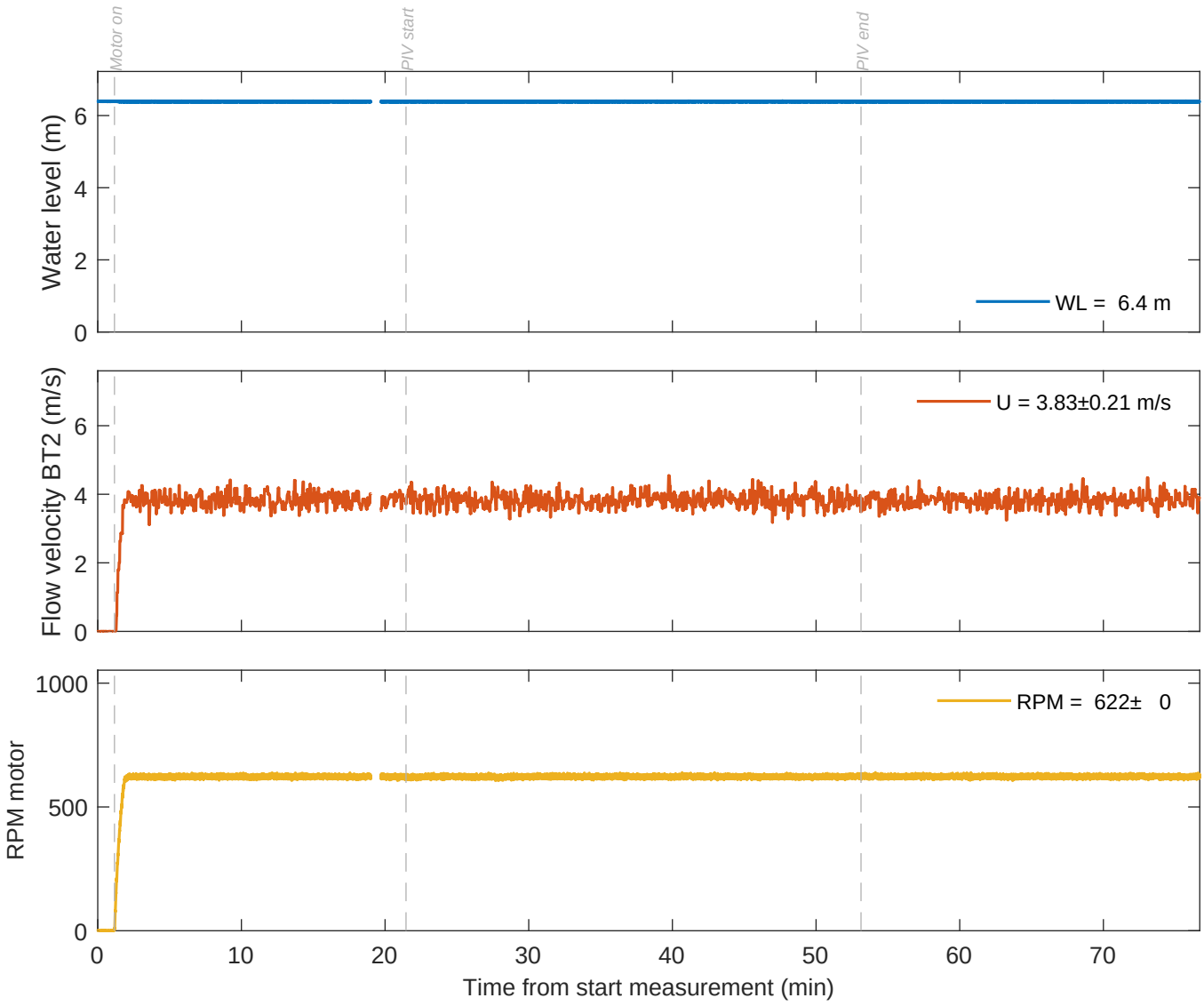
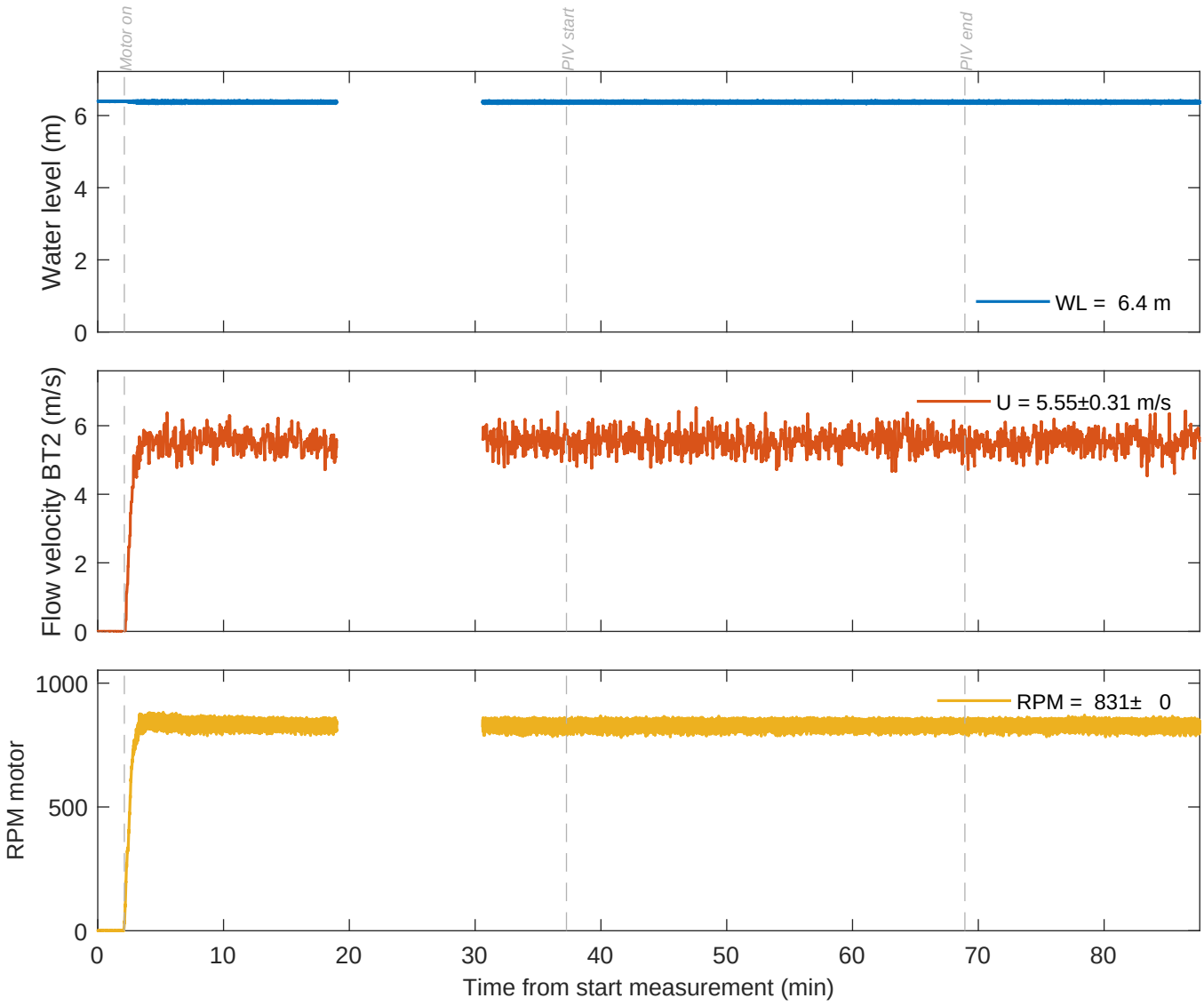


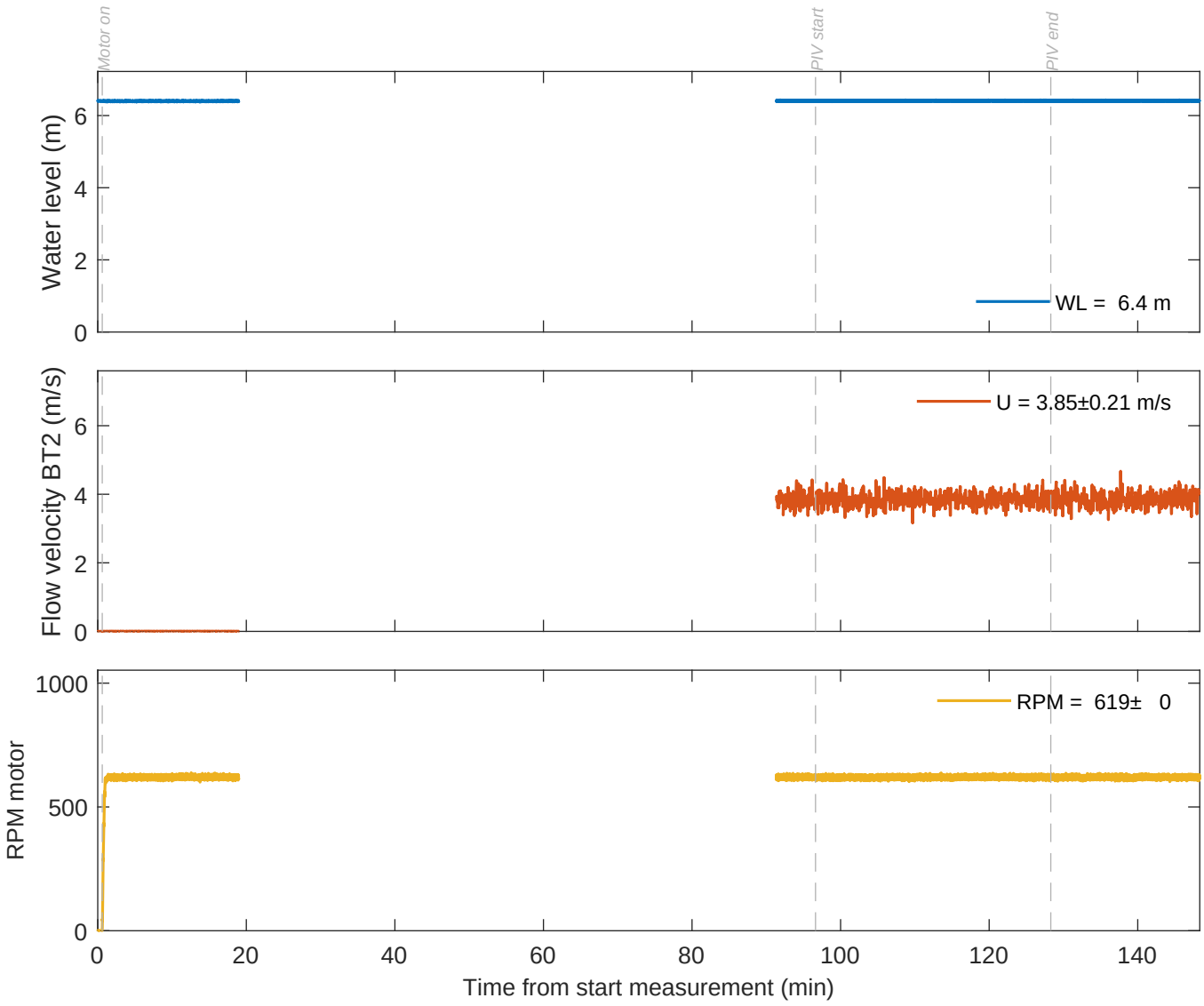
Water level, flow velocity BT2, RPM motor Active thruster: BT2 Δx = 23.1 m, Δy = 0.0 m, UKC = 2.4 m, U_{BT2} = 2.6 m/s	Measurement signals	TKI-SOP
	PIVSOP008	
Deltares	11206641	Fig. C



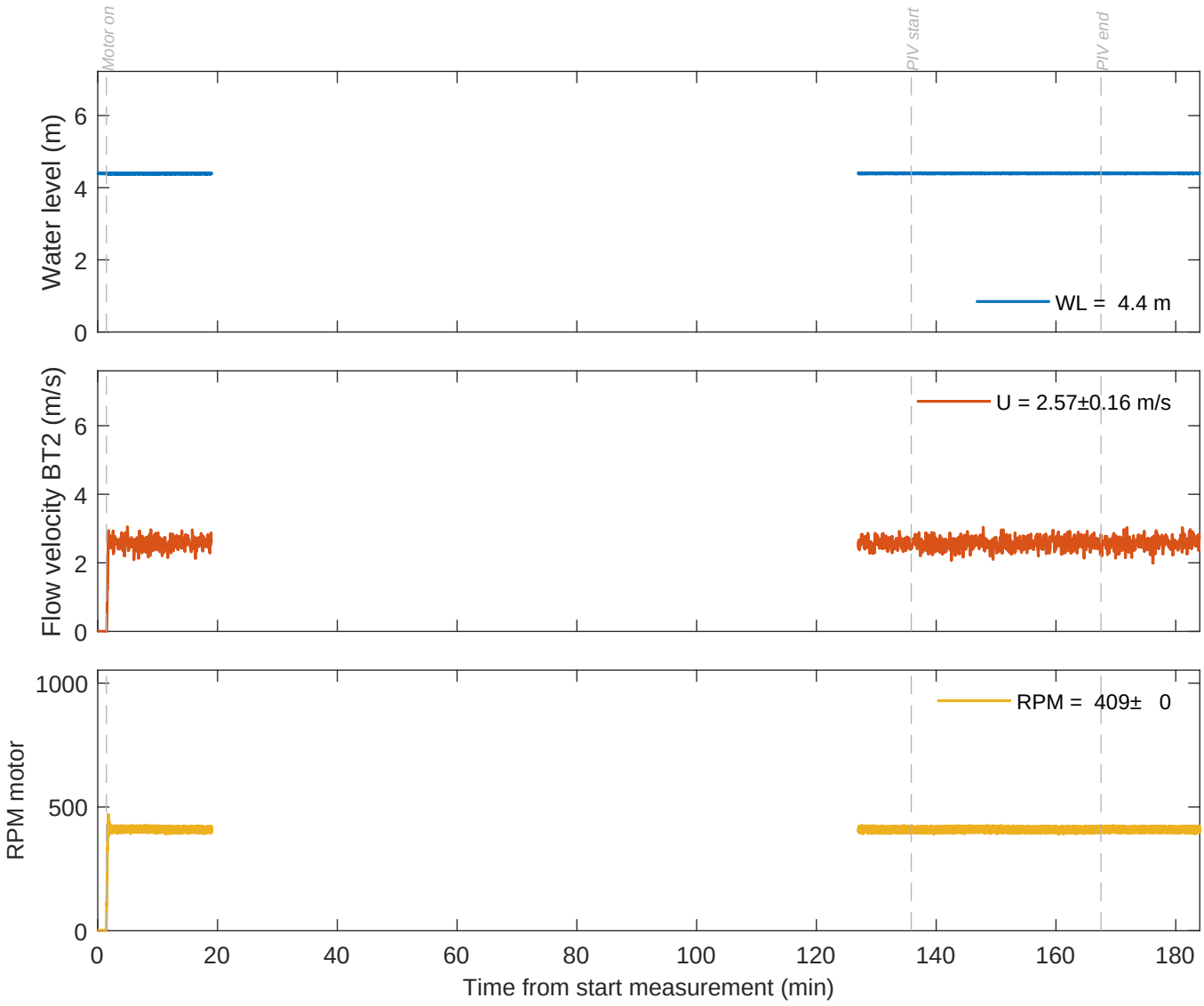
Water level, flow velocity BT2, RPM motor Active thruster: BT2 Δx = 23.1 m, Δy = 0.0 m, UKC = 2.4 m, U_{BT2} = 3.8 m/s	Measurement signals	TKI-SOP
	PIVSOP011	
Deltares	11206641	Fig. C



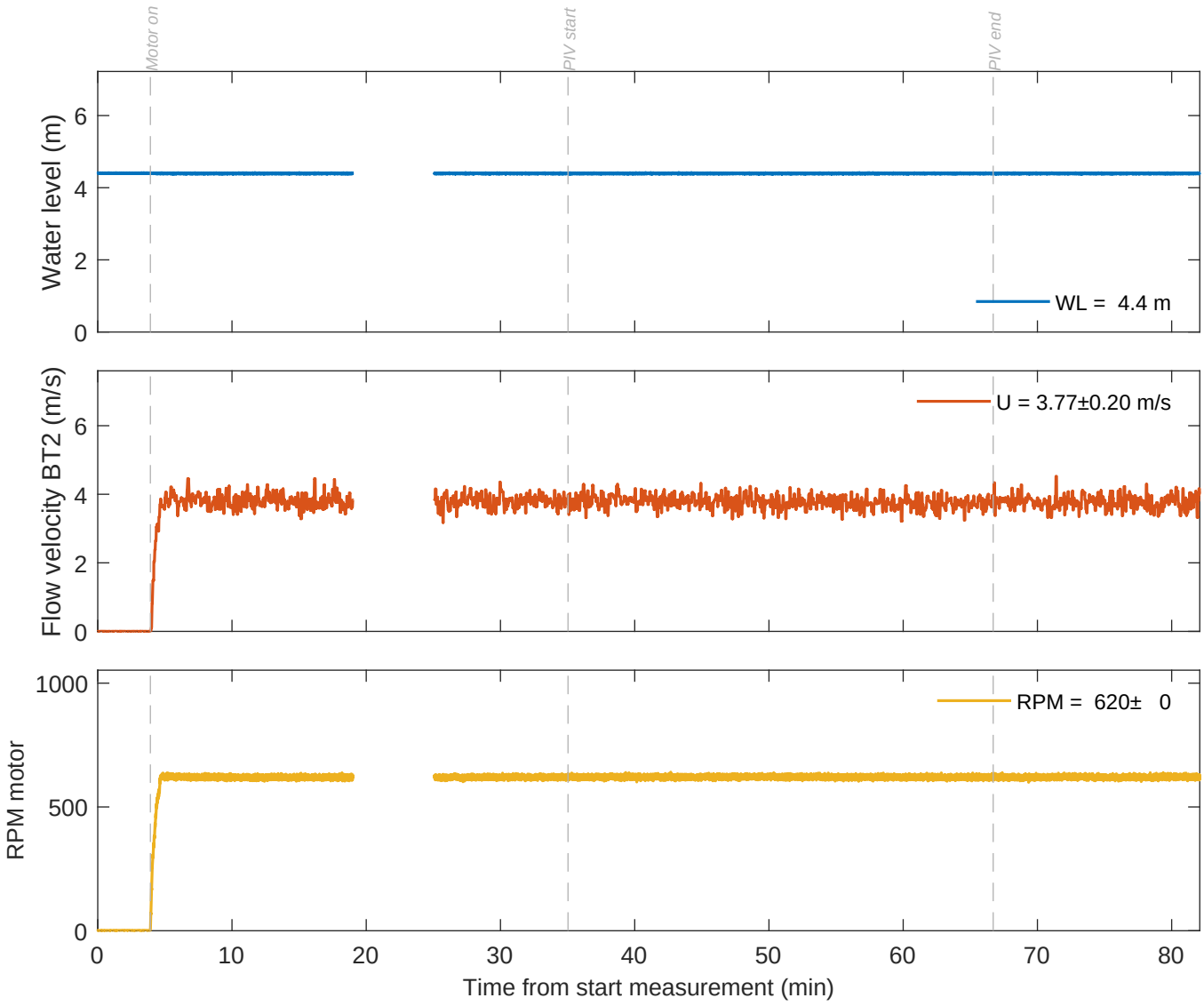
Water level, flow velocity BT2, RPM motor Active thruster: BT2 Δx = 23.1 m, Δy = 0.0 m, UKC = 2.4 m, U_{BT2} = 5.6 m/s	Measurement signals	TKI-SOP
	PIVSOP014	
Deltares	11206641	Fig. C



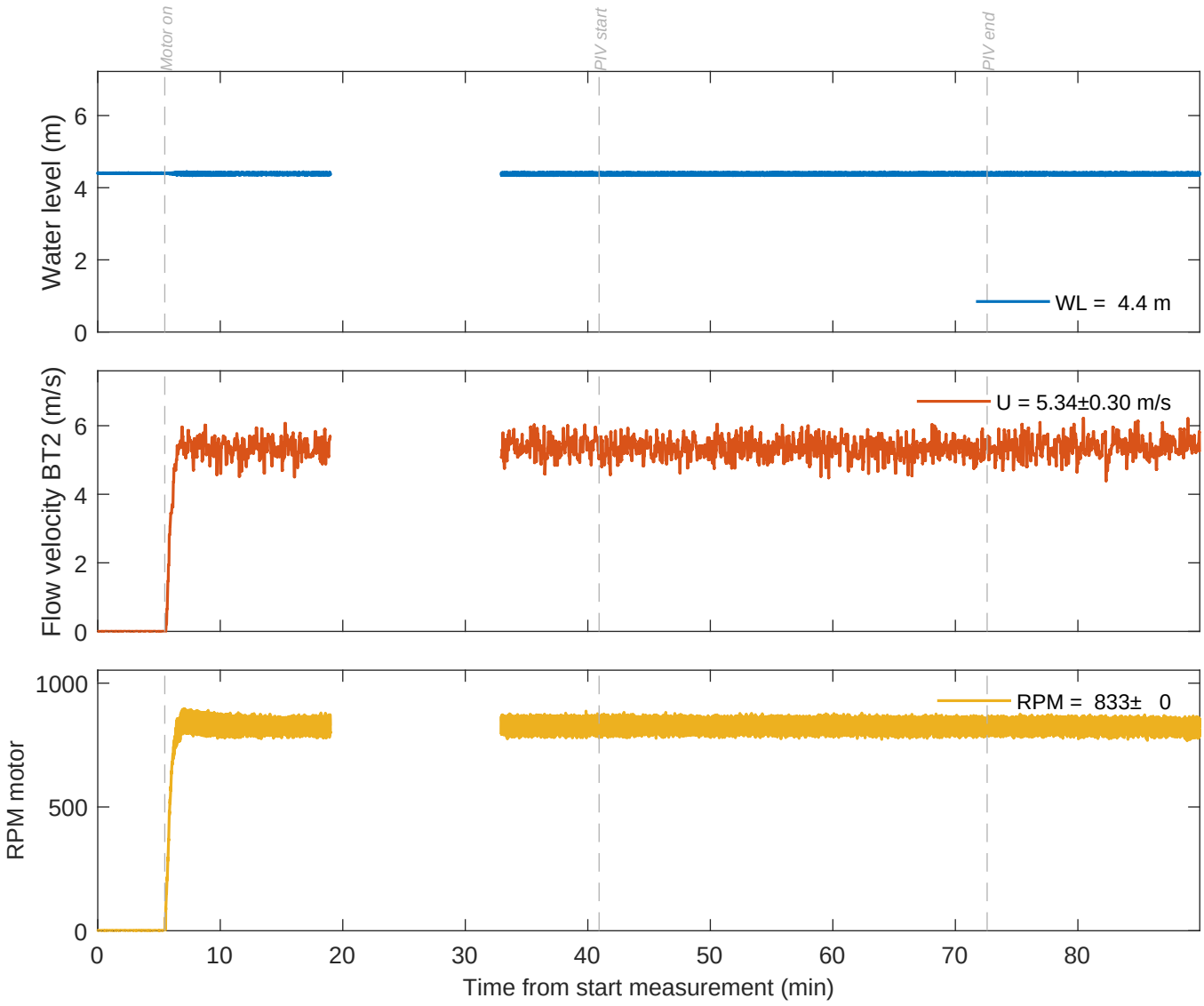
Water level, flow velocity BT2, RPM motor Active thruster: BT2 Δx = 23.1 m, Δy = 0.0 m, UKC = 2.4 m, U_{BT2} = 3.9 m/s	Measurement signals	TKI-SOP
	PIVSOP017	
Deltares	11206641	Fig. C



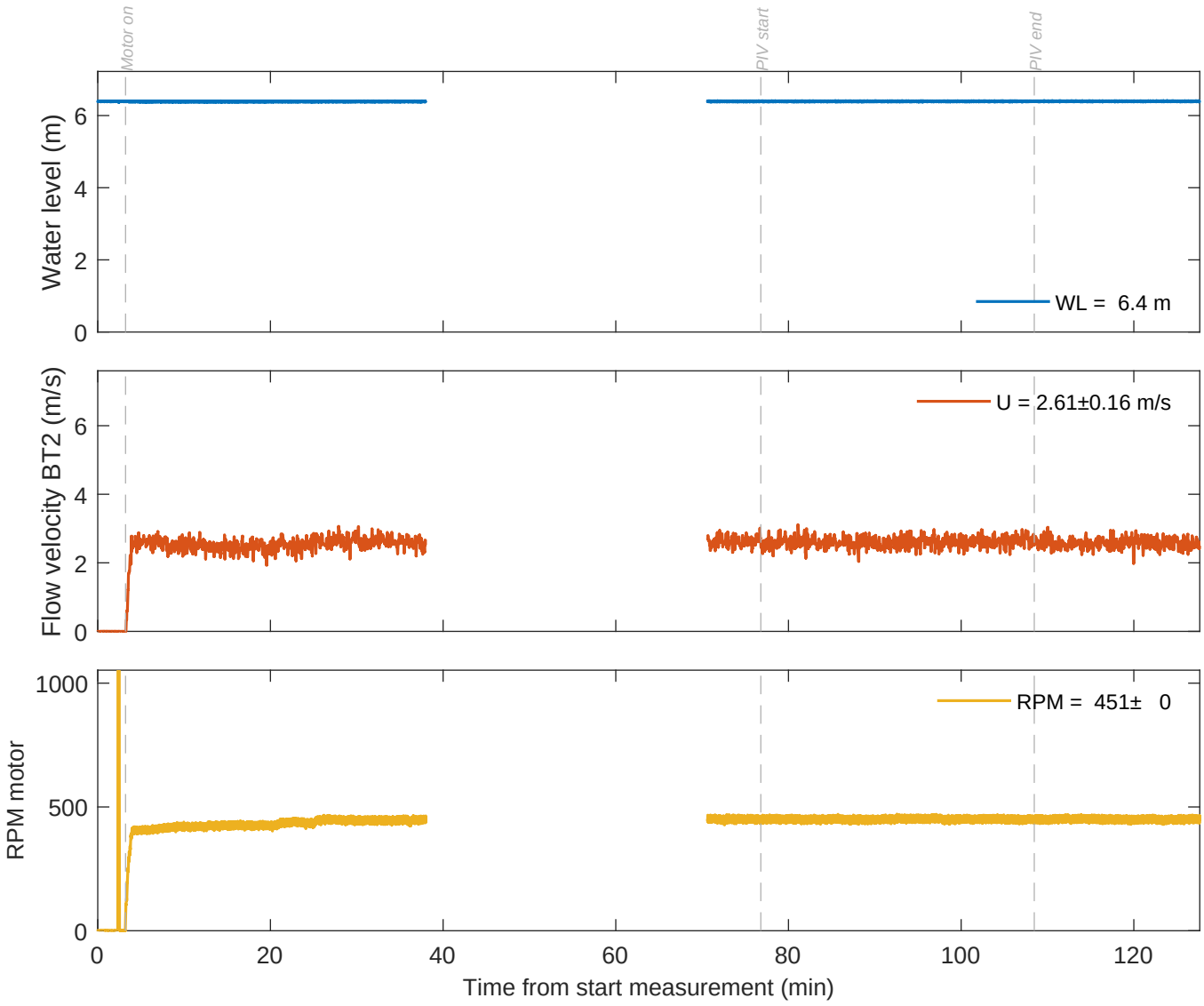
Water level, flow velocity BT2, RPM motor Active thruster: BT2 Δx = 23.1 m, Δy = 0.0 m, UKC = 0.5 m, U_{BT2} = 2.6 m/s	Measurement signals	TKI-SOP
	PIVSOP020	
Deltares	11206641	Fig. C



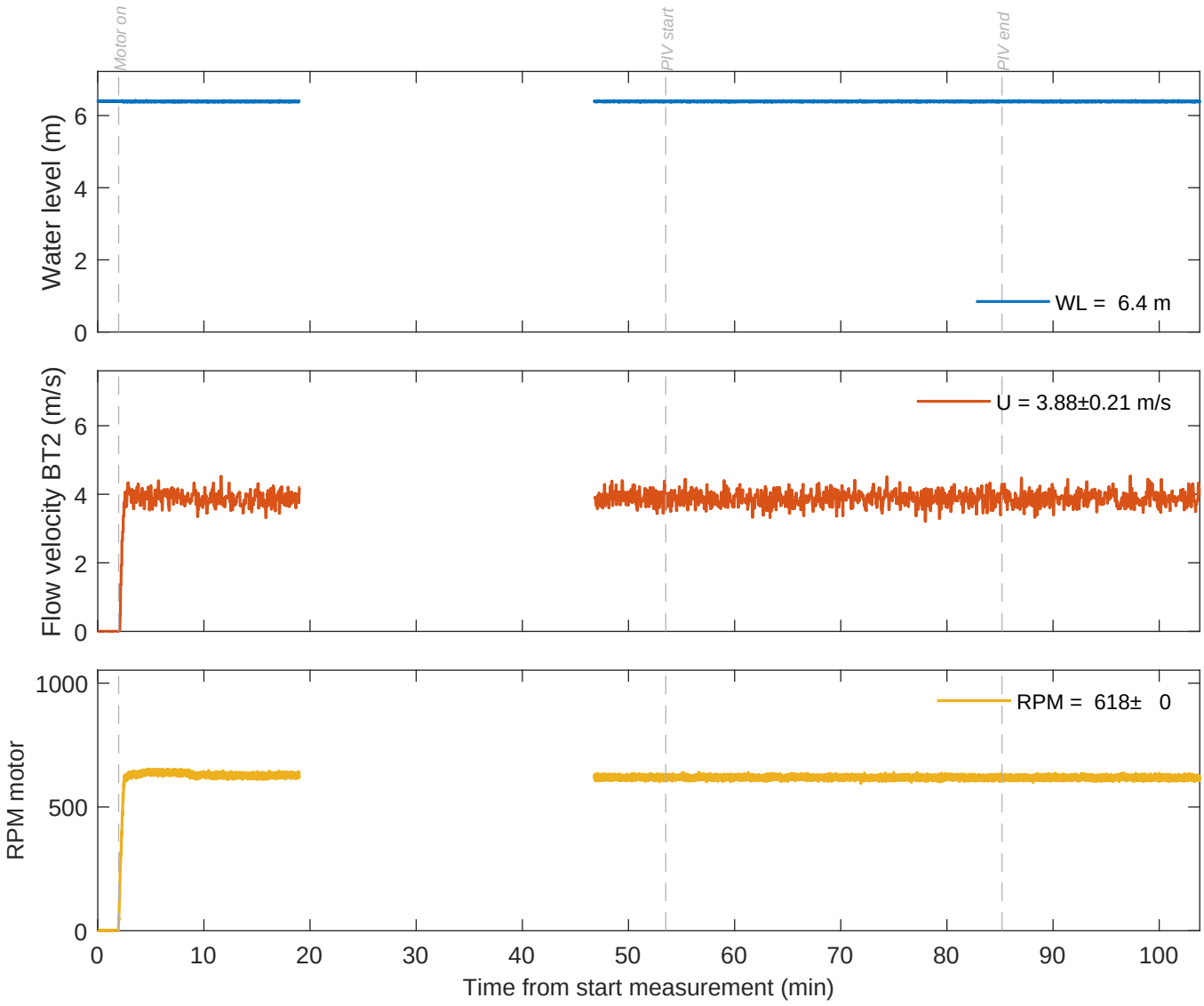
Water level, flow velocity BT2, RPM motor Active thruster: BT2 Δx = 23.1 m, Δy = 0.0 m, UKC = 0.5 m, U_{BT2} = 3.8 m/s	Measurement signals	TKI-SOP
	PIVSOP023	
Deltares	11206641	Fig. C



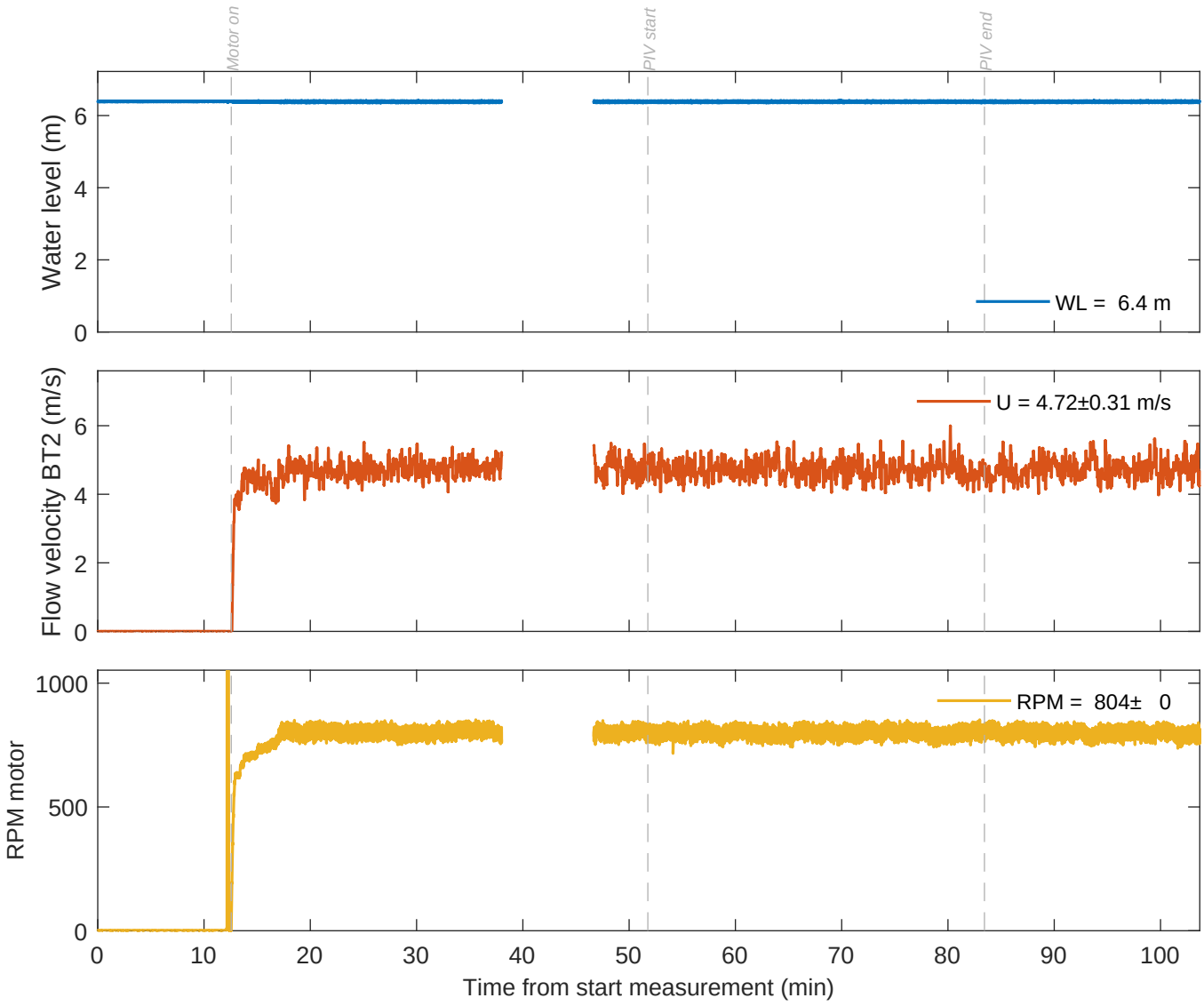
Water level, flow velocity BT2, RPM motor Active thruster: BT2 Δx = 23.1 m, Δy = 0.0 m, UKC = 0.5 m, U_{BT2} = 5.3 m/s	Measurement signals	TKI-SOP
	PIVSOP026	
Deltares	11206641	Fig. C



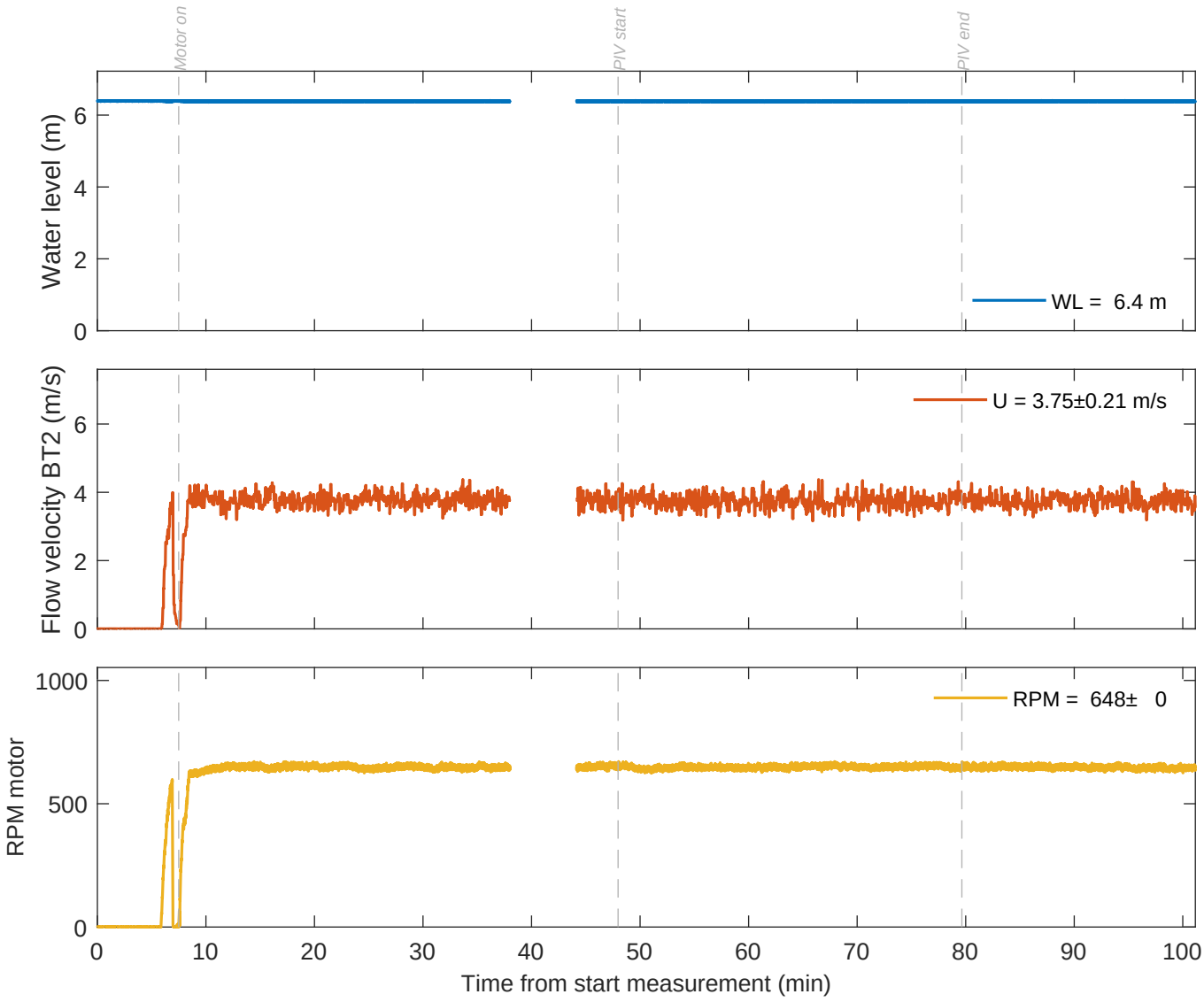
Water level, flow velocity BT2, RPM motor Active thruster: BT2 Δx = 0.8 m, Δy = 0.0 m, UKC = 2.4 m, U_{BT2} = 2.6 m/s	Measurement signals	TKI-SOP
	PIVSOP029	
Deltares	11206641	Fig. C



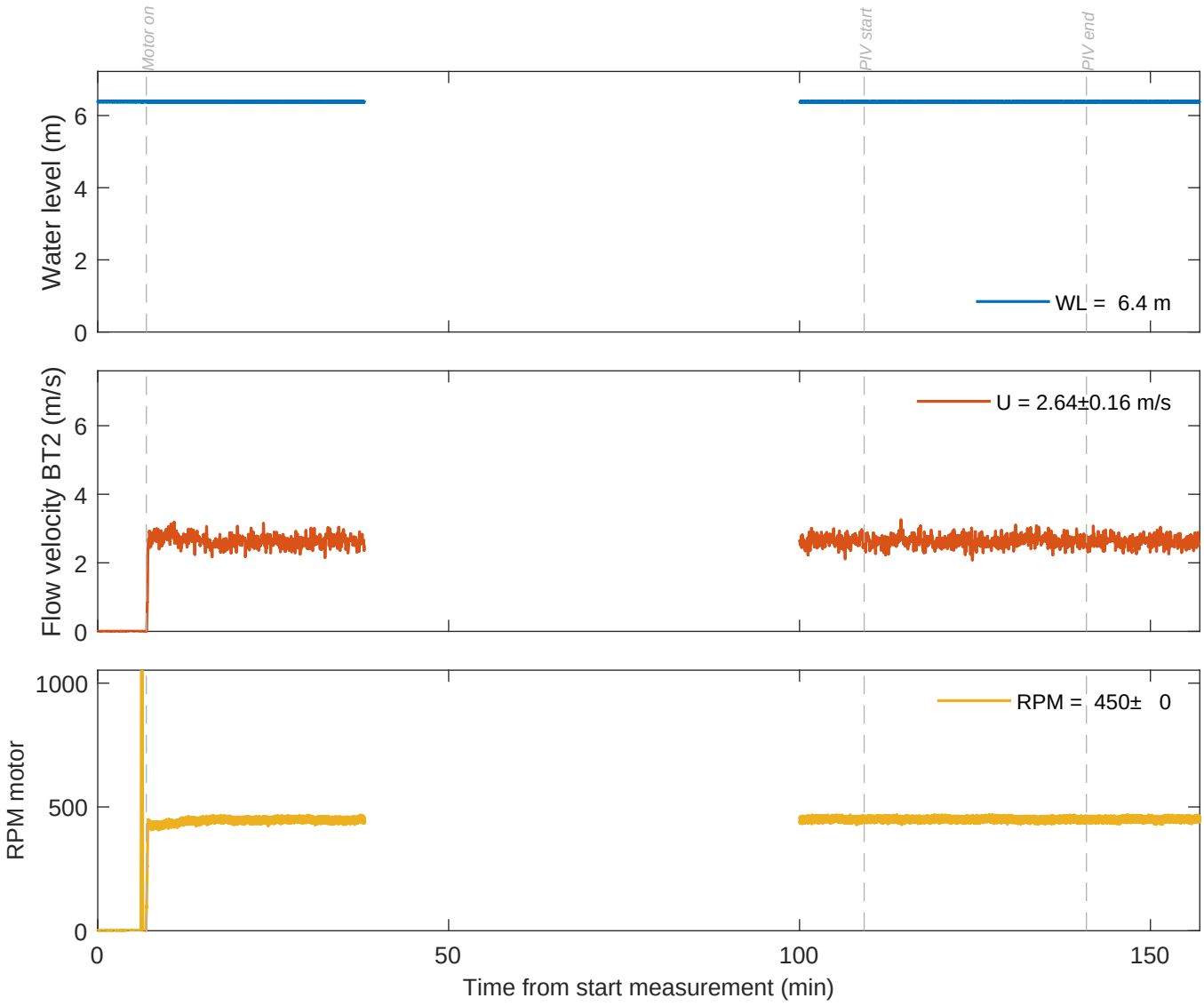
Water level, flow velocity BT2, RPM motor Active thruster: BT2 Δx = 0.8 m, Δy = 0.0 m, UKC = 2.4 m, U_{BT2} = 3.9 m/s	Measurement signals	TKI-SOP
	PIVSOP032	
Deltares	11206641	Fig. C



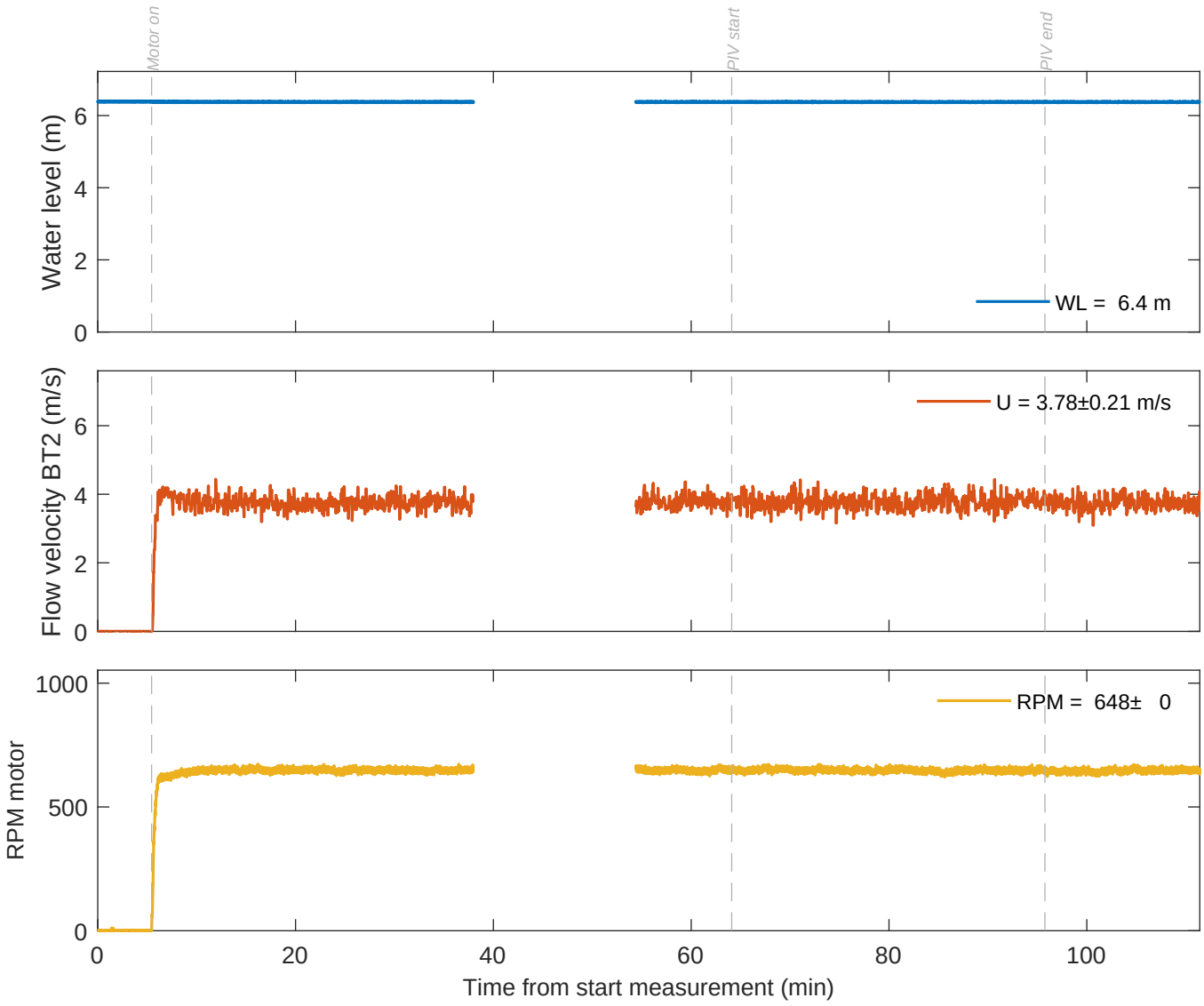
Water level, flow velocity BT2, RPM motor Active thruster: BT2 Δx = 0.8 m, Δy = 0.0 m, UKC = 2.4 m, U_{BT2} = 4.7 m/s	Measurement signals	TKI-SOP
	PIVSOP037	
Deltares	11206641	Fig. C



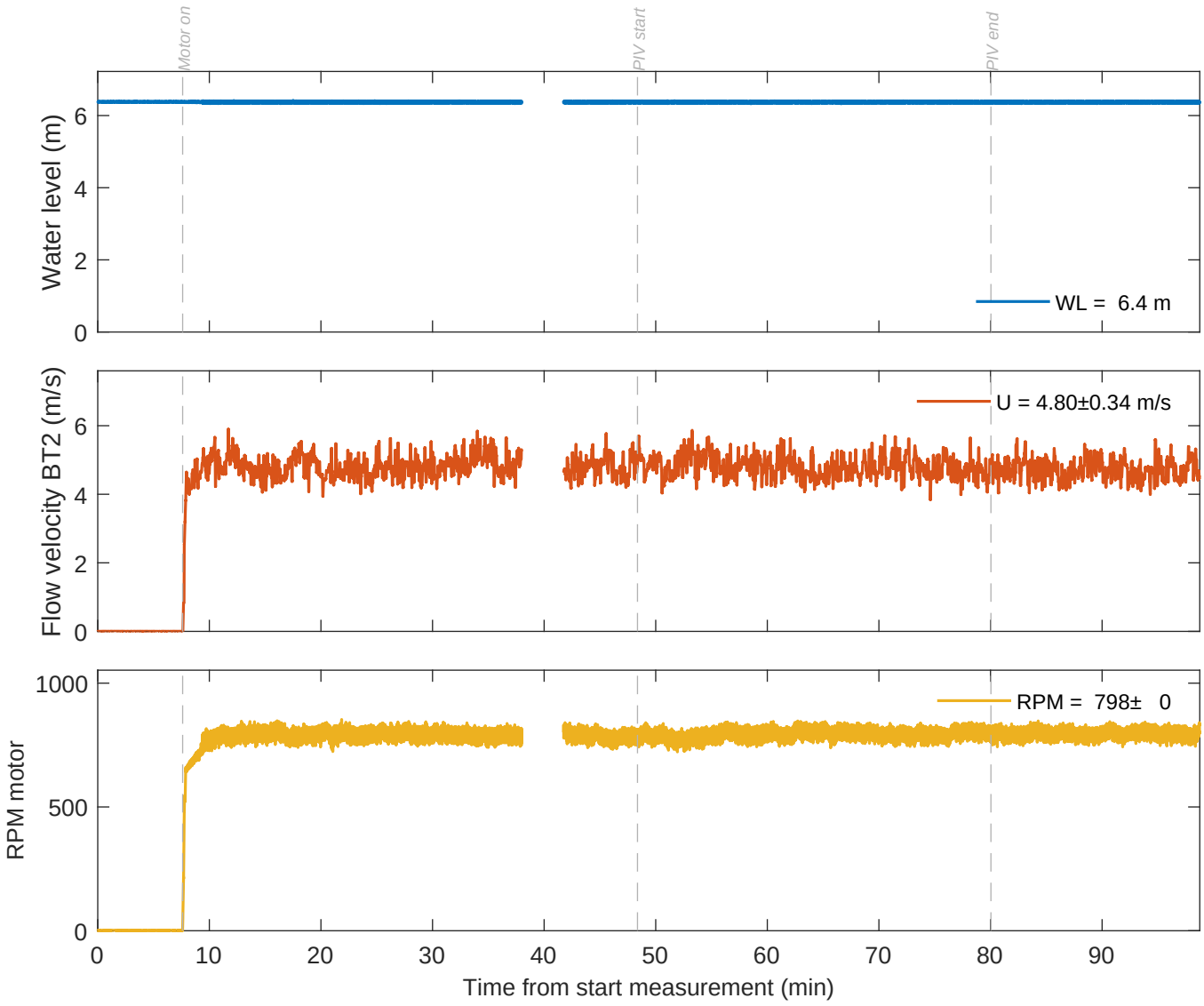
Water level, flow velocity BT2, RPM motor Active thruster: BT2 Δx = 0.8 m, Δy = 0.0 m, UKC = 2.4 m, U_{BT2} = 3.7 m/s	Measurement signals	TKI-SOP
	PIVSOP040	
Deltares	11206641	Fig. C



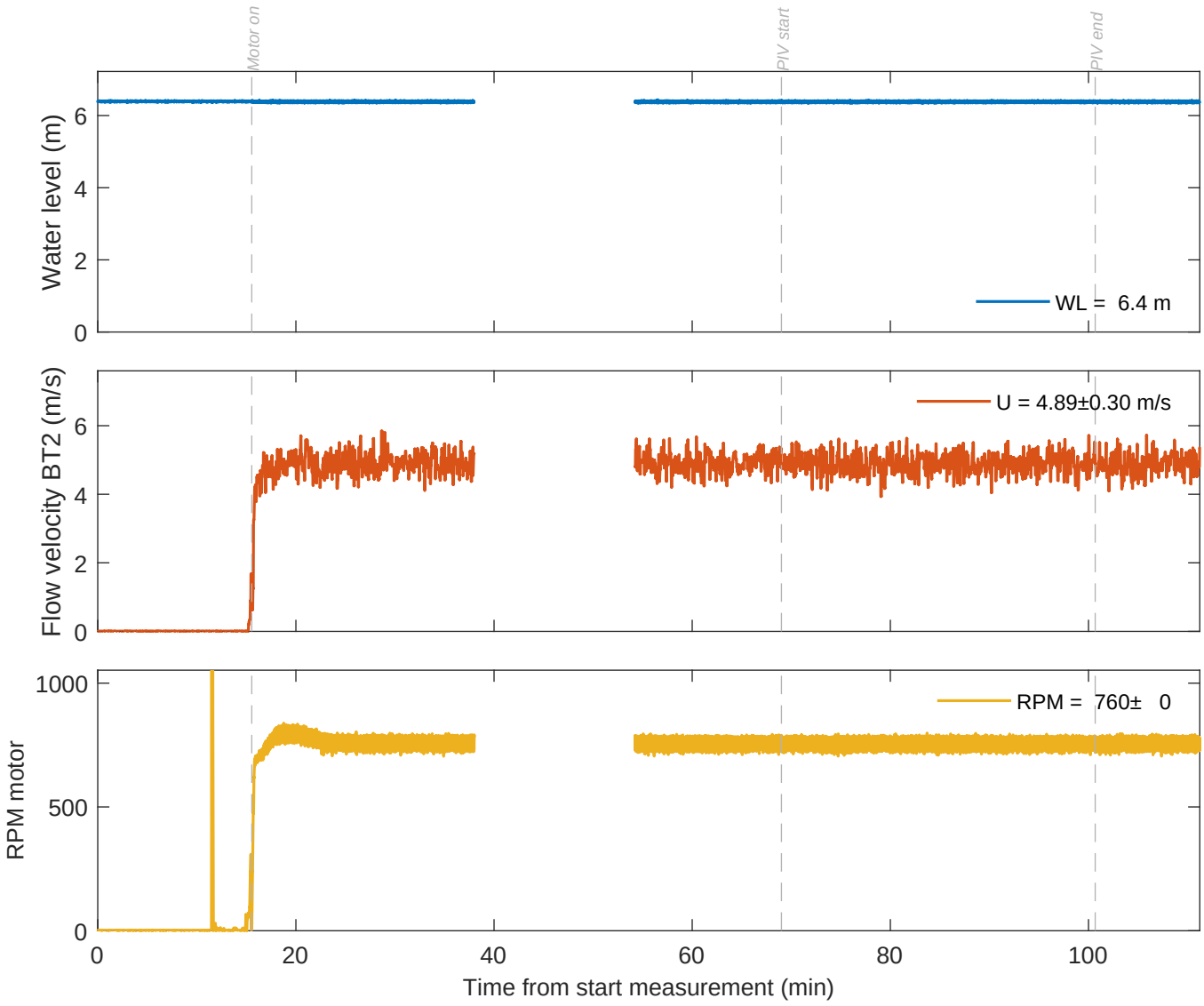
Water level, flow velocity BT2, RPM motor Active thruster: BT2 Δx = 0.8 m, Δy = 0.0 m, UKC = 2.4 m, U_{BT2} = 2.6 m/s	Measurement signals	TKI-SOP
	PIVSOP052	
Deltares	11206641	Fig. C



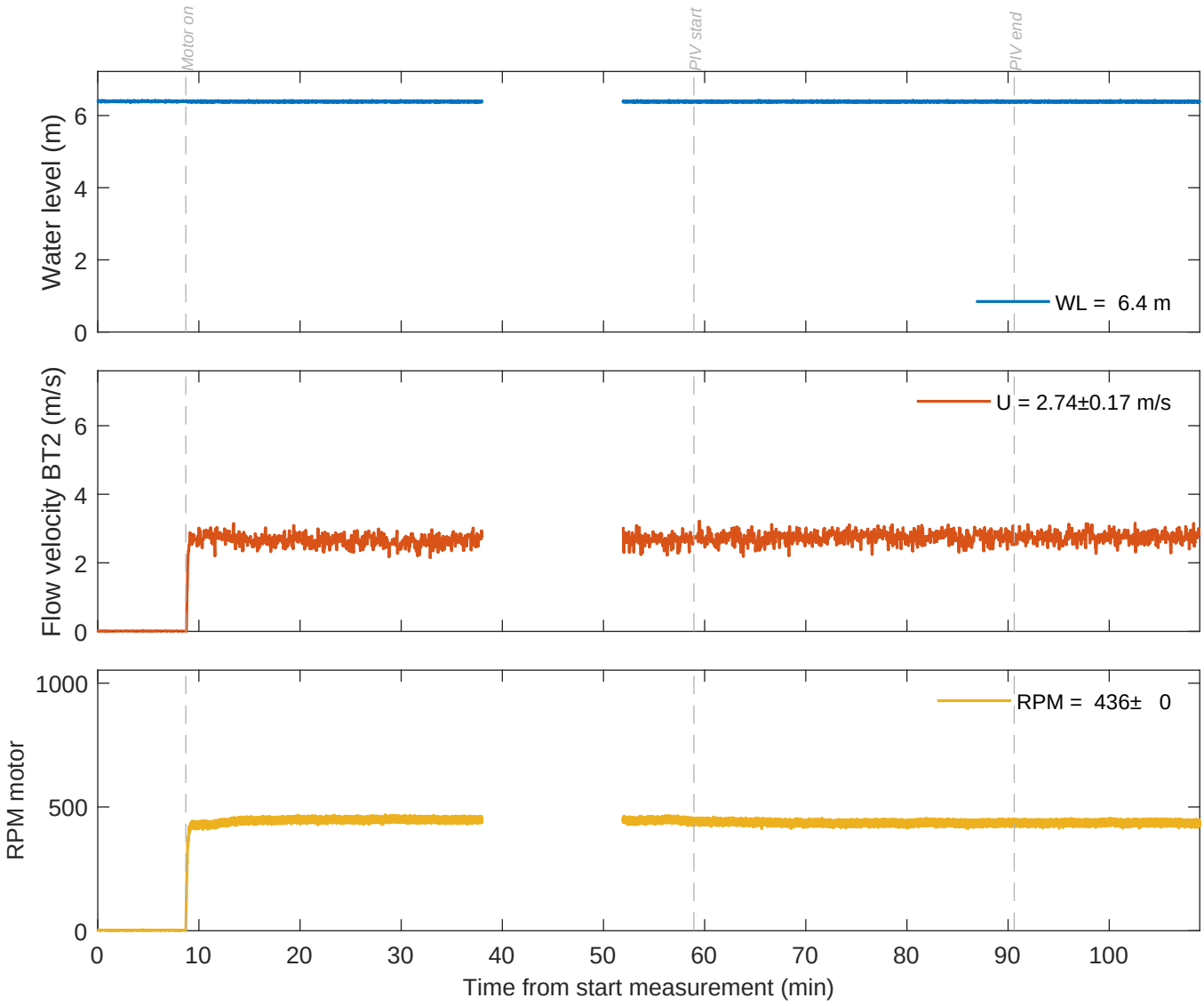
Water level, flow velocity BT2, RPM motor Active thruster: BT2 Δx = 0.8 m, Δy = 0.0 m, UKC = 2.4 m, U_{BT2} = 3.8 m/s	Measurement signals	TKI-SOP
	PIVSOP055	
Deltares	11206641	Fig. C



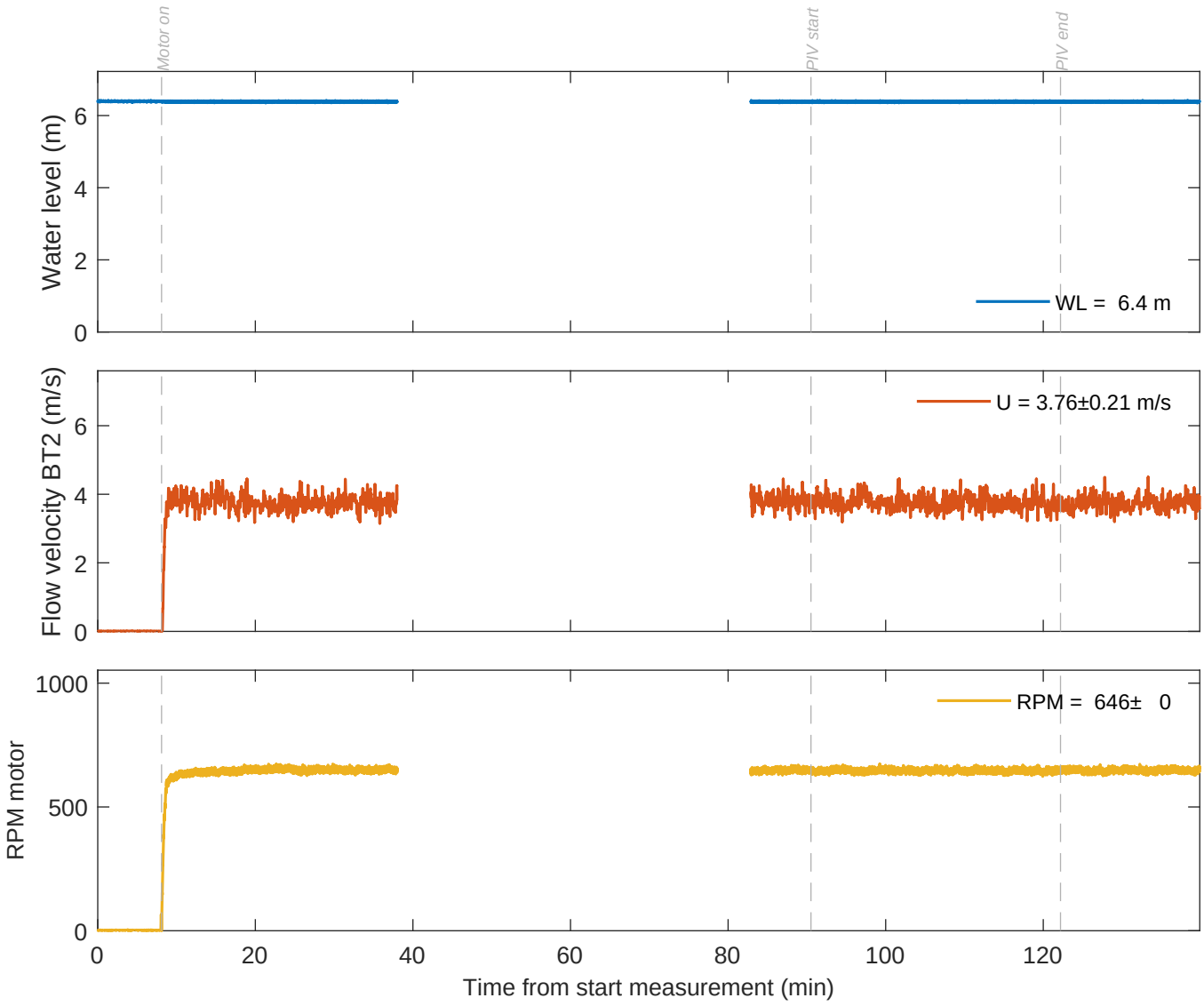
Water level, flow velocity BT2, RPM motor Active thruster: BT2 Δx = 0.8 m, Δy = 0.0 m, UKC = 2.4 m, U_{BT2} = 4.8 m/s	Measurement signals	TKI-SOP
	PIVSOP057	
Deltares	11206641	Fig. C



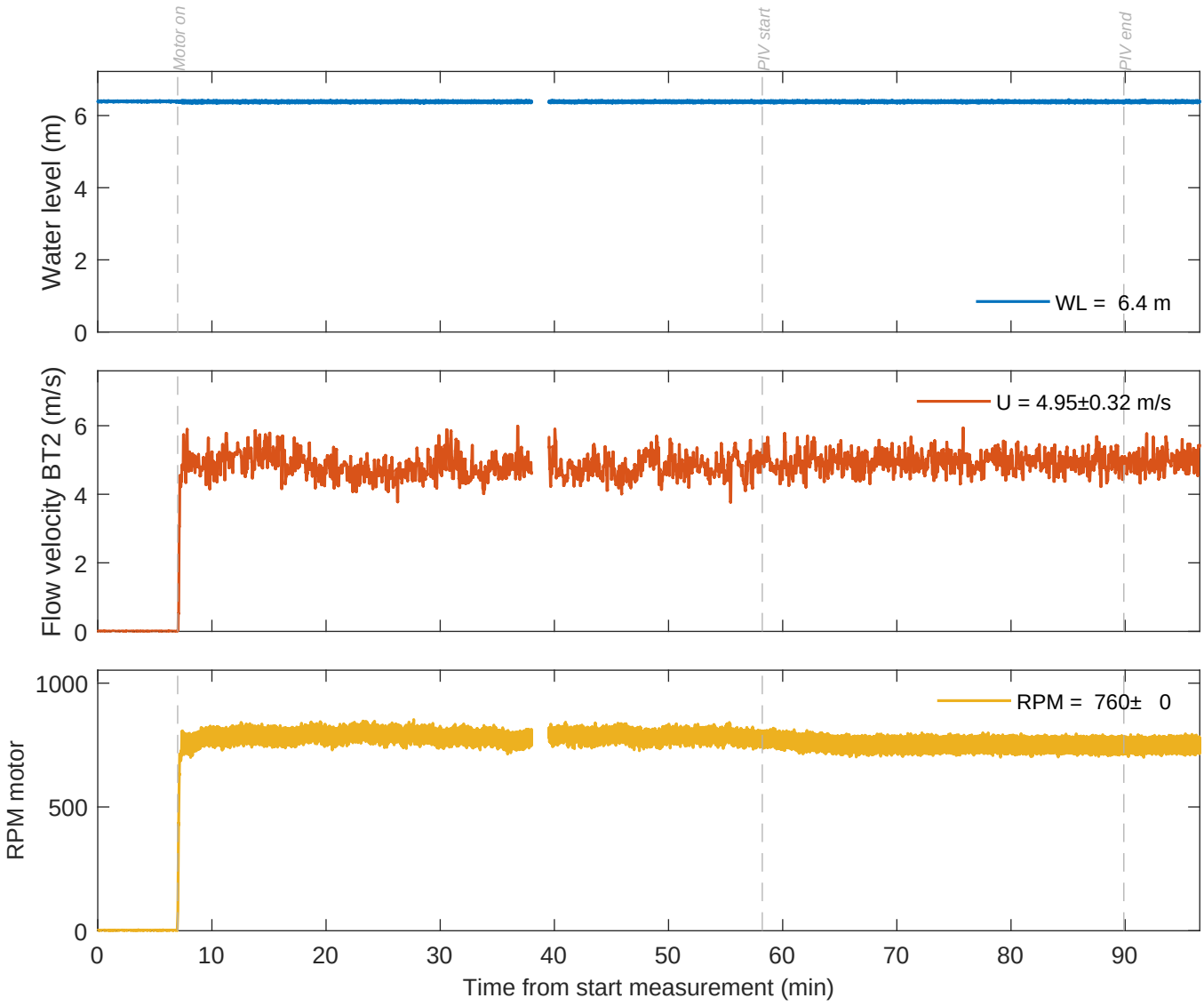
Water level, flow velocity BT2, RPM motor Active thruster: BT2 Δx = 0.8 m, Δy = 0.0 m, UKC = 2.4 m, U_{BT2} = 4.9 m/s	Measurement signals	TKI-SOP
	PIVSOP060	
Deltares	11206641	Fig. C



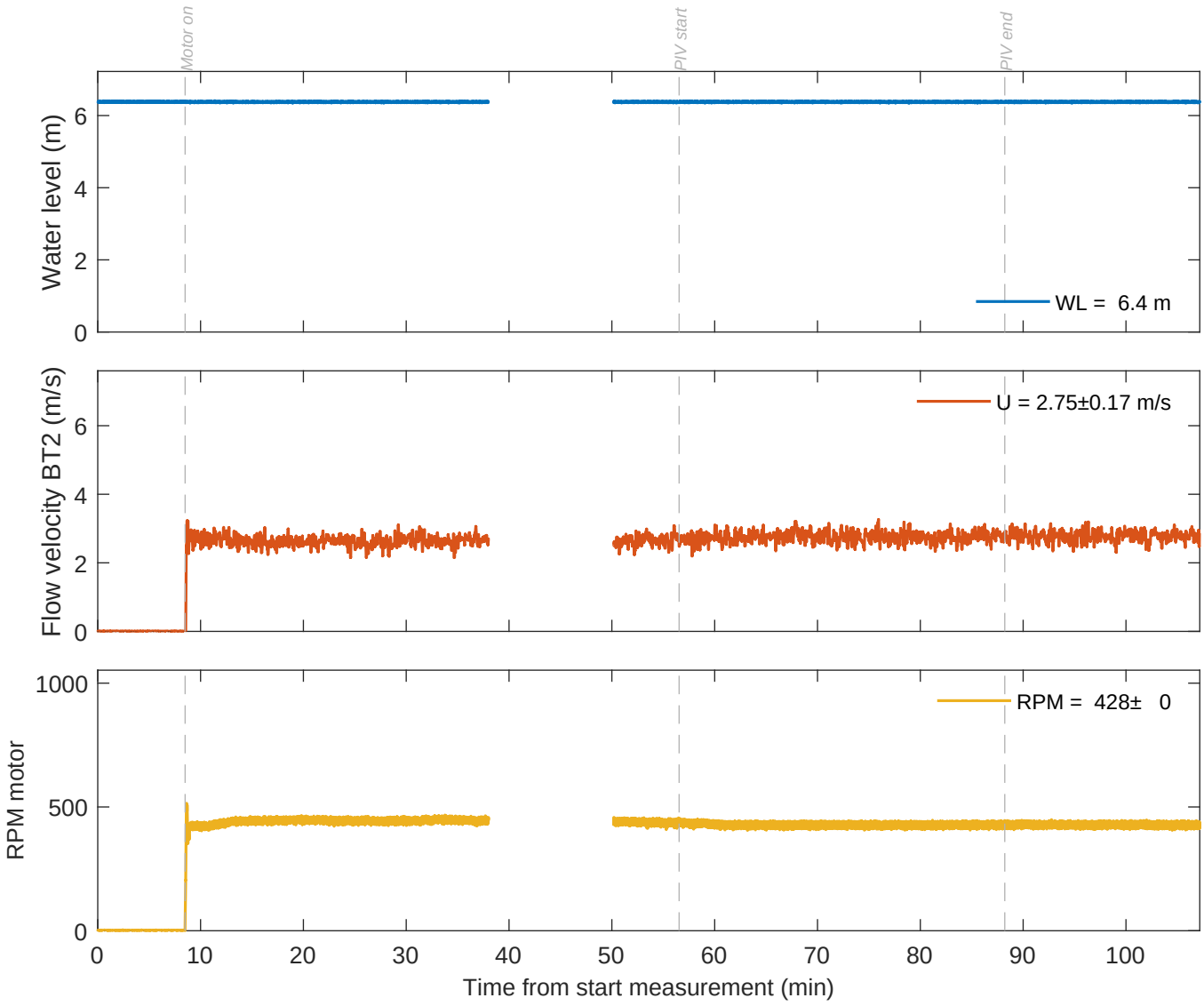
Water level, flow velocity BT2, RPM motor Active thruster: BT2 Δx = 0.8 m, Δy = 2.0 m, UKC = 2.4 m, U_{BT2} = 2.7 m/s	Measurement signals	TKI-SOP
	PIVSOP063	
Deltares	11206641	Fig. C



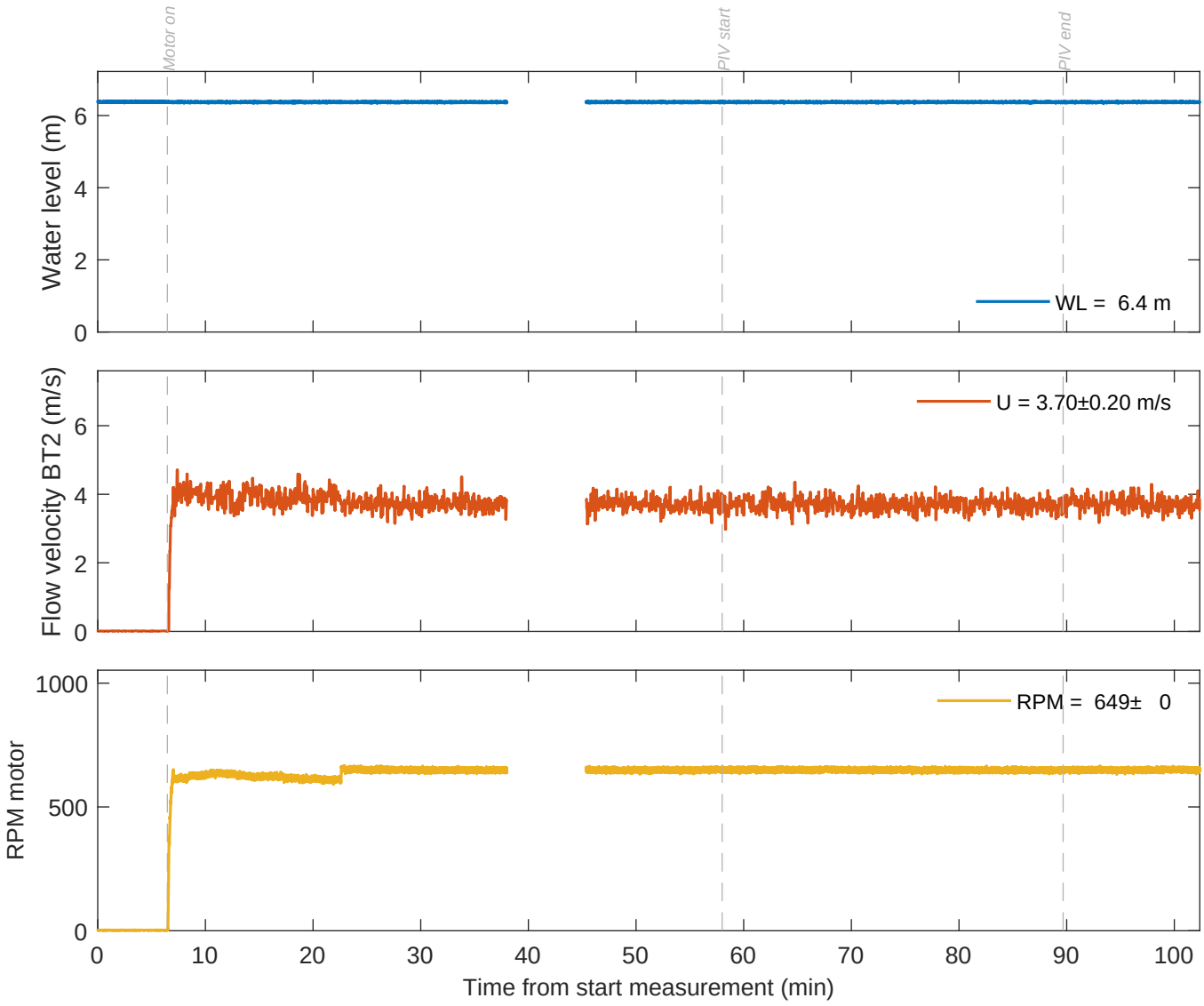
Water level, flow velocity BT2, RPM motor Active thruster: BT2 Δx = 0.8 m, Δy = 2.0 m, UKC = 2.4 m, U_{BT2} = 3.8 m/s	Measurement signals	TKI-SOP
	PIVSOP065	
Deltares	11206641	Fig. C



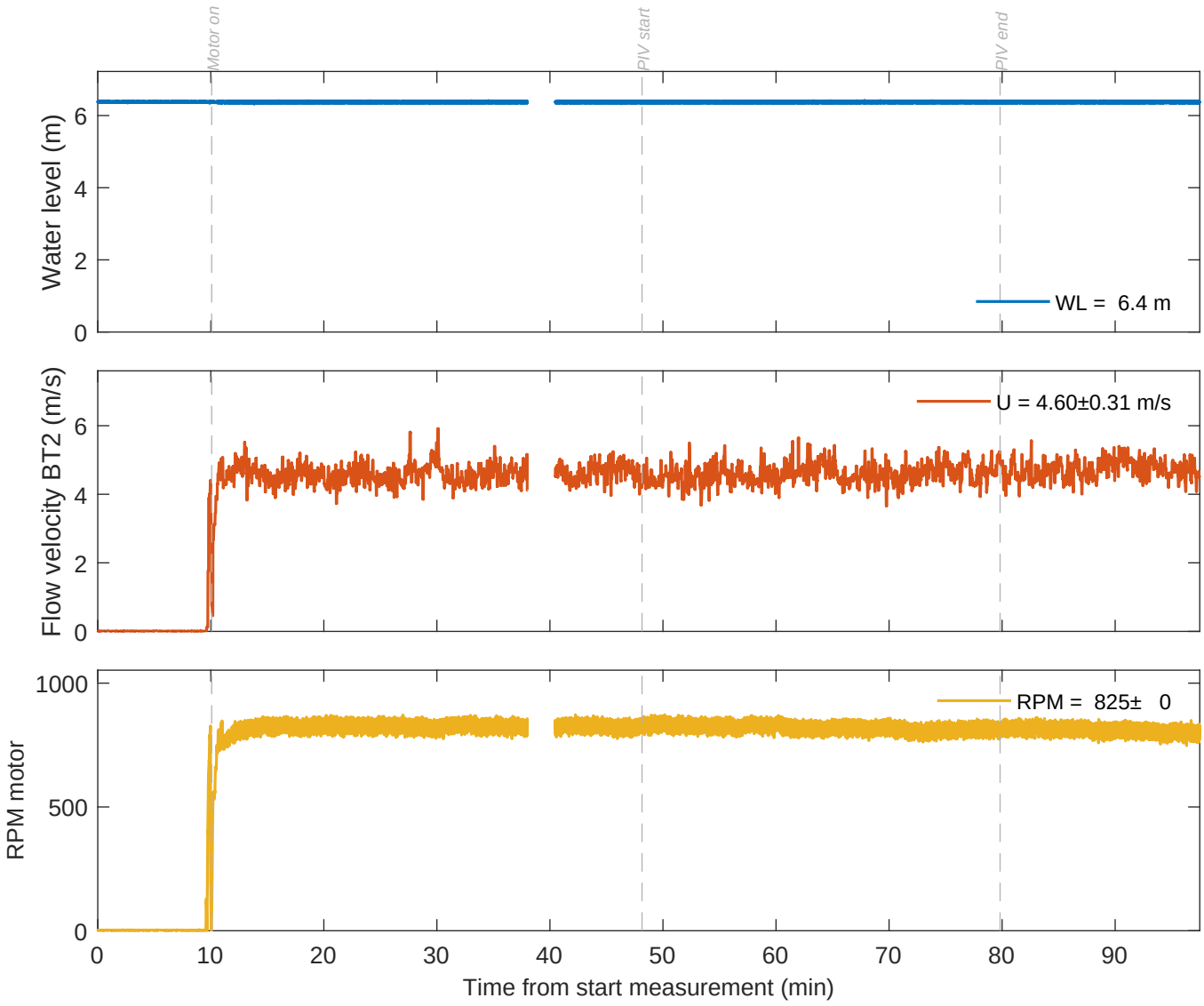
Water level, flow velocity BT2, RPM motor Active thruster: BT2 Δx = 0.8 m, Δy = 2.0 m, UKC = 2.4 m, U_{BT2} = 4.9 m/s	Measurement signals	TKI-SOP
	PIVSOP067	
Deltares	11206641	Fig. C



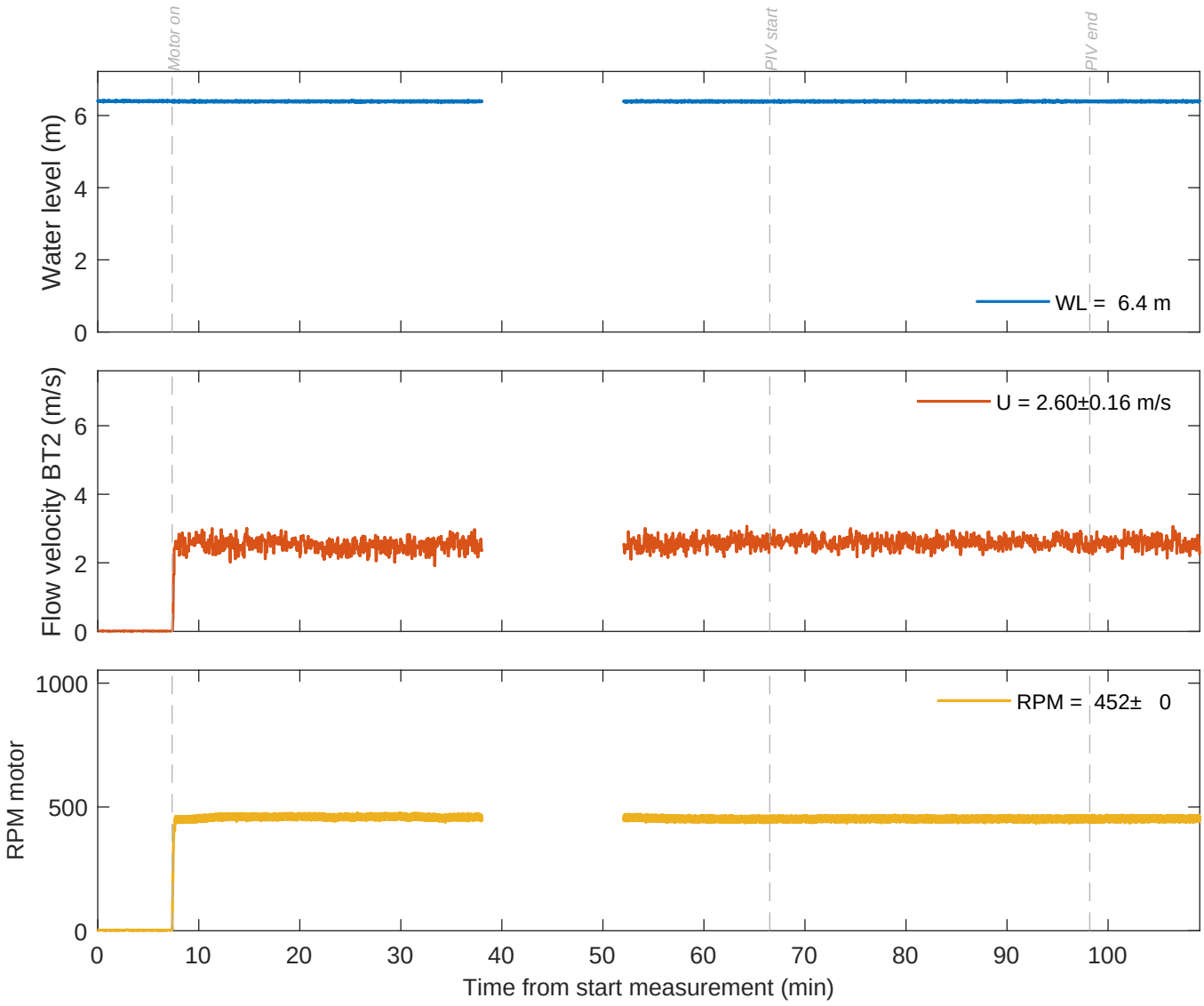
Water level, flow velocity BT2, RPM motor Active thruster: BT2 Δx = 0.8 m, Δy = 3.5 m, UKC = 2.4 m, U_{BT2} = 2.8 m/s	Measurement signals	TKI-SOP
	PIVSOP070	
Deltares	11206641	Fig. C



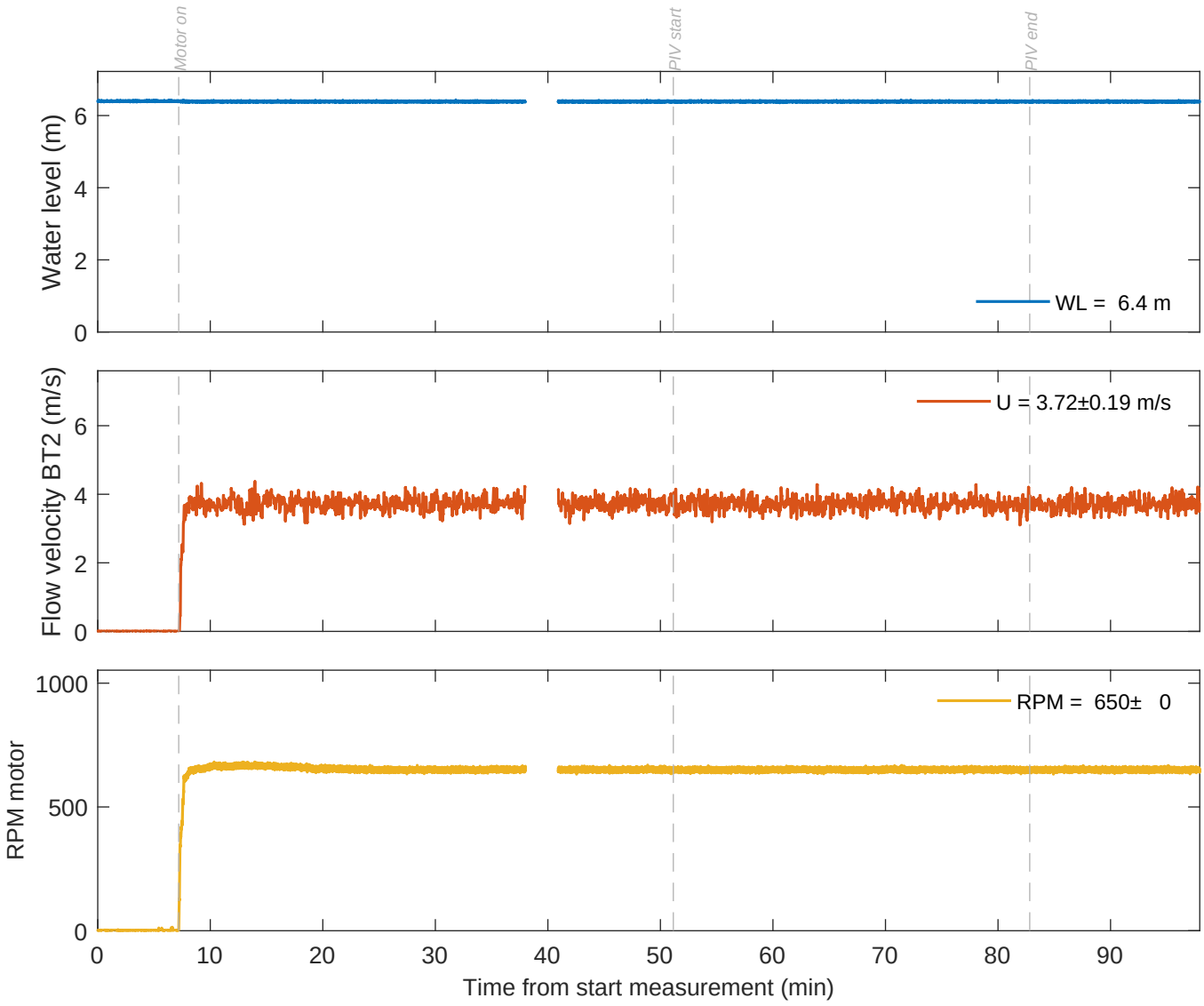
Water level, flow velocity BT2, RPM motor Active thruster: BT2 Δx = 0.8 m, Δy = 3.5 m, UKC = 2.4 m, U_{BT2} = 3.7 m/s	Measurement signals	TKI-SOP
	PIVSOP072	
Deltares	11206641	Fig. C



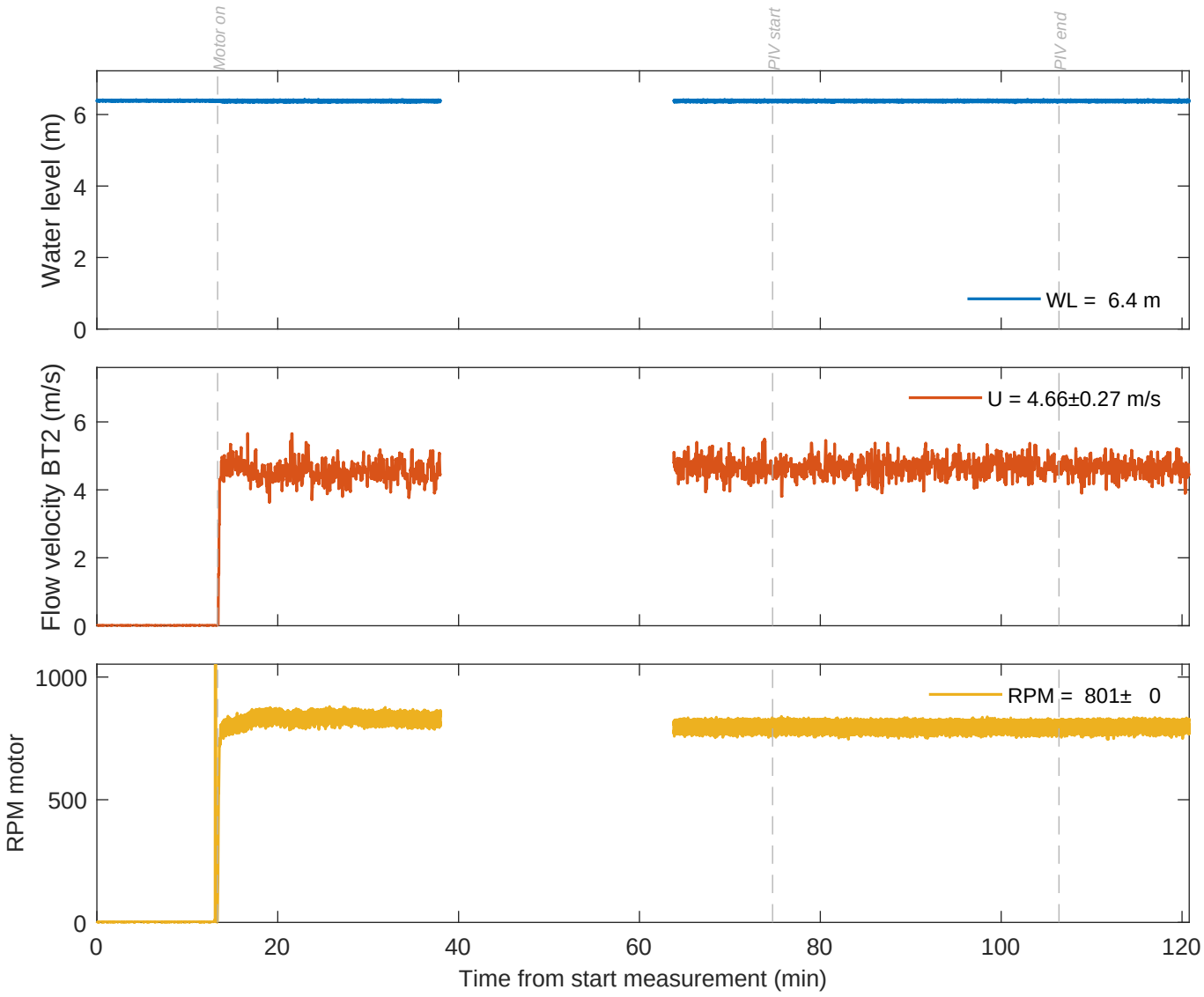
Water level, flow velocity BT2, RPM motor Active thruster: BT2 Δx = 0.8 m, Δy = 3.5 m, UKC = 2.4 m, U_{BT2} = 4.6 m/s	Measurement signals	TKI-SOP
	PIVSOP074	
Deltares	11206641	Fig. C



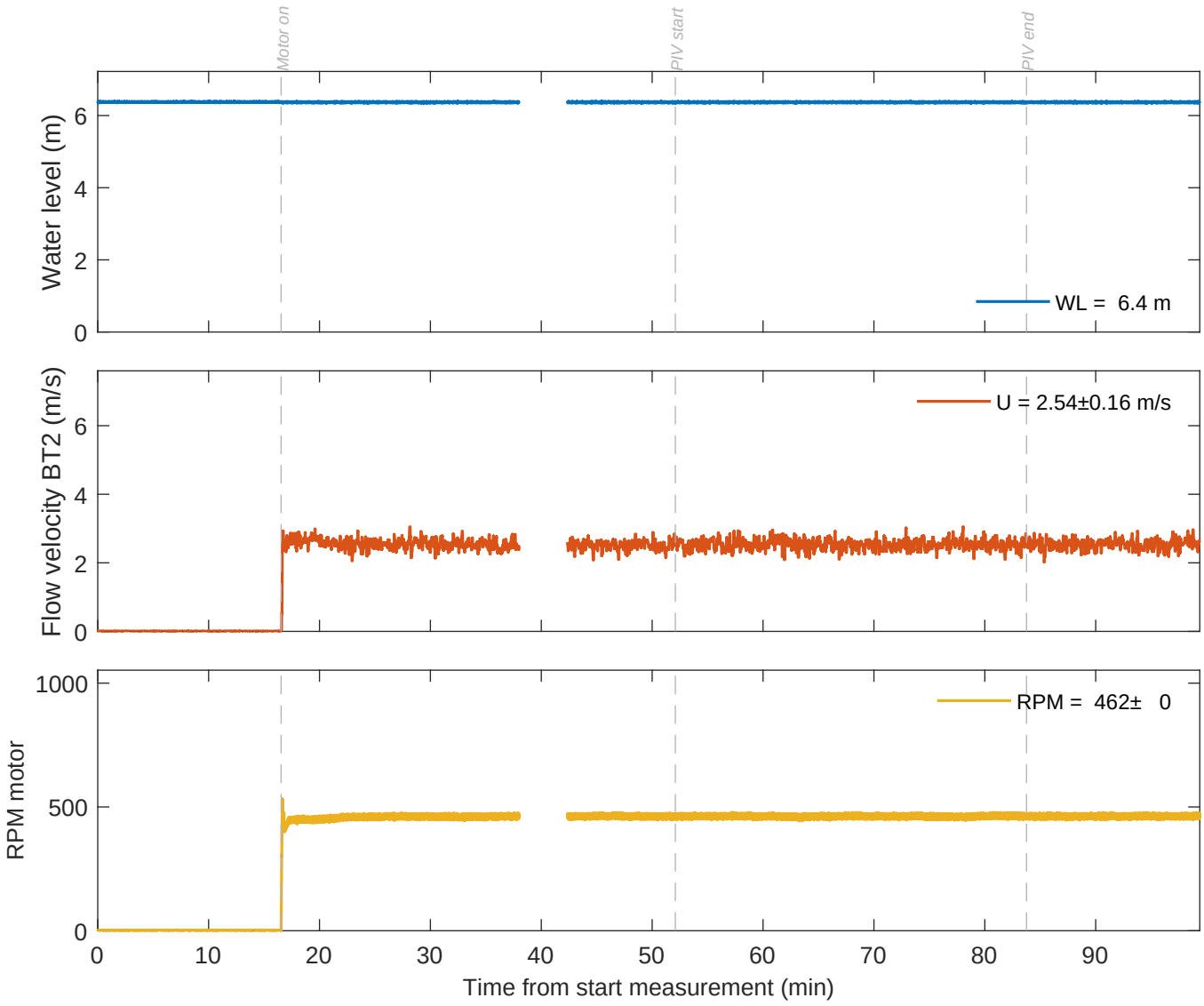
Water level, flow velocity BT2, RPM motor Active thruster: BT2 Δx = 0.8 m, Δy = -2.0 m, UKC = 2.5 m, U_{BT2} = 2.6 m/s	Measurement signals	TKI-SOP
	PIVSOP077	
Deltares	11206641	Fig. C



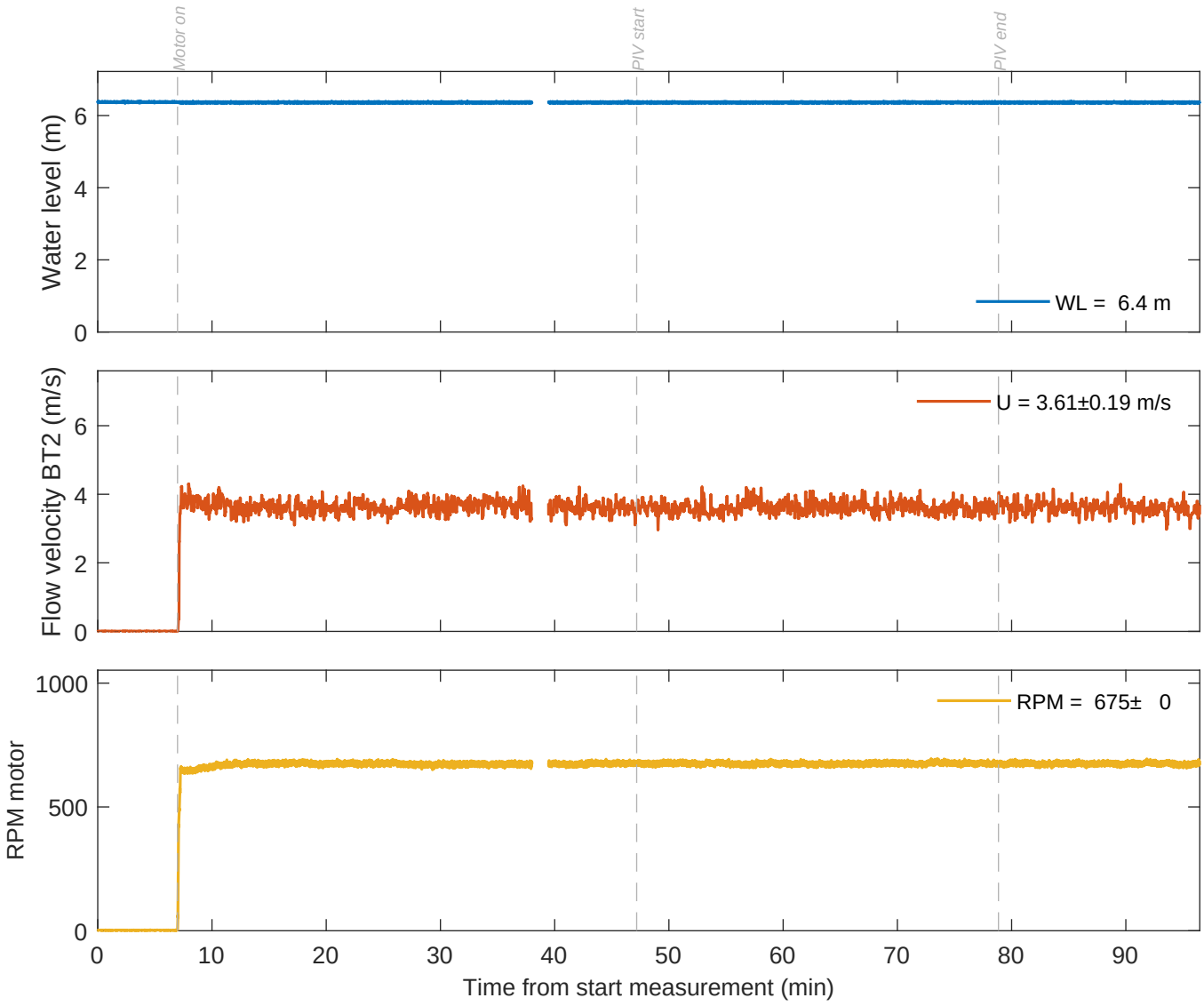
Water level, flow velocity BT2, RPM motor Active thruster: BT2 Δx = 0.8 m, Δy = -2.0 m, UKC = 2.5 m, U_{BT2} = 3.7 m/s	Measurement signals	TKI-SOP
	PIVSOP079	
Deltares	11206641	Fig. C



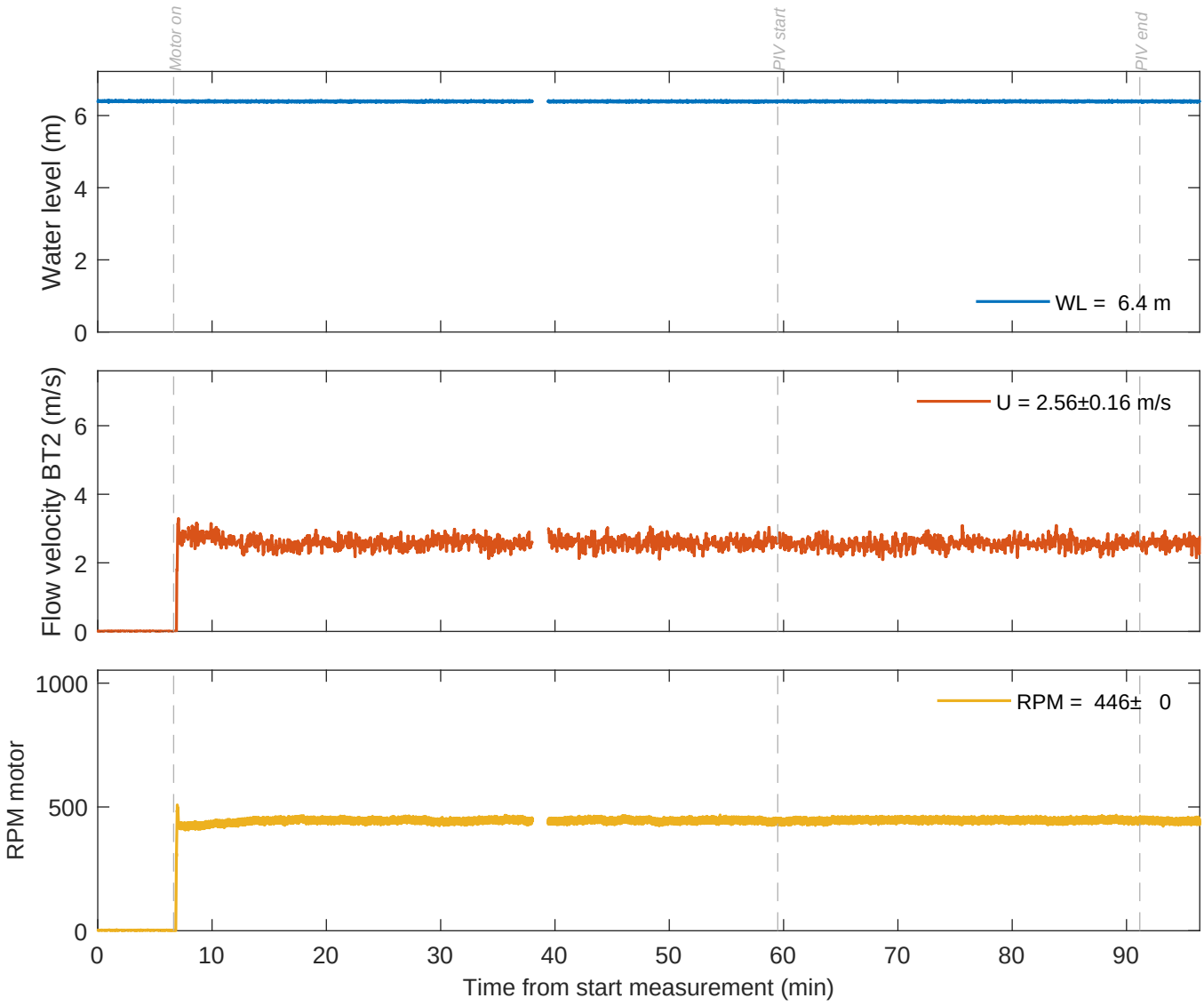
Water level, flow velocity BT2, RPM motor Active thruster: BT2 Δx = 0.8 m, Δy = -2.0 m, UKC = 2.5 m, U_{BT2} = 4.7 m/s	Measurement signals	TKI-SOP
	PIVSOP082	
Deltares	11206641	Fig. C



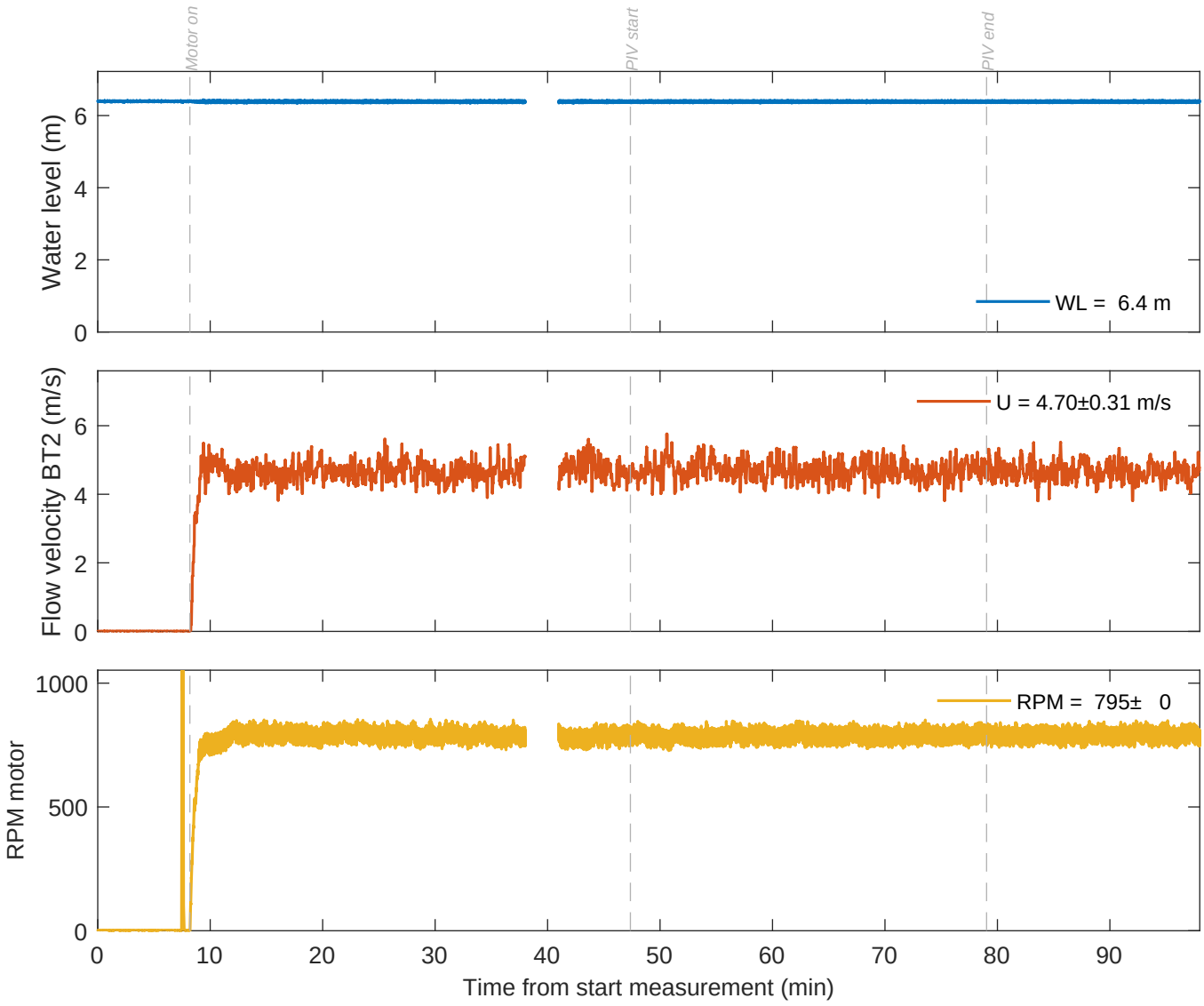
Water level, flow velocity BT2, RPM motor Active thruster: BT2 Δx = 0.8 m, Δy = -4.0 m, UKC = 2.5 m, U_{BT2} = 2.5 m/s	Measurement signals	TKI-SOP
	PIVSOP085	
Deltares	11206641	Fig. C



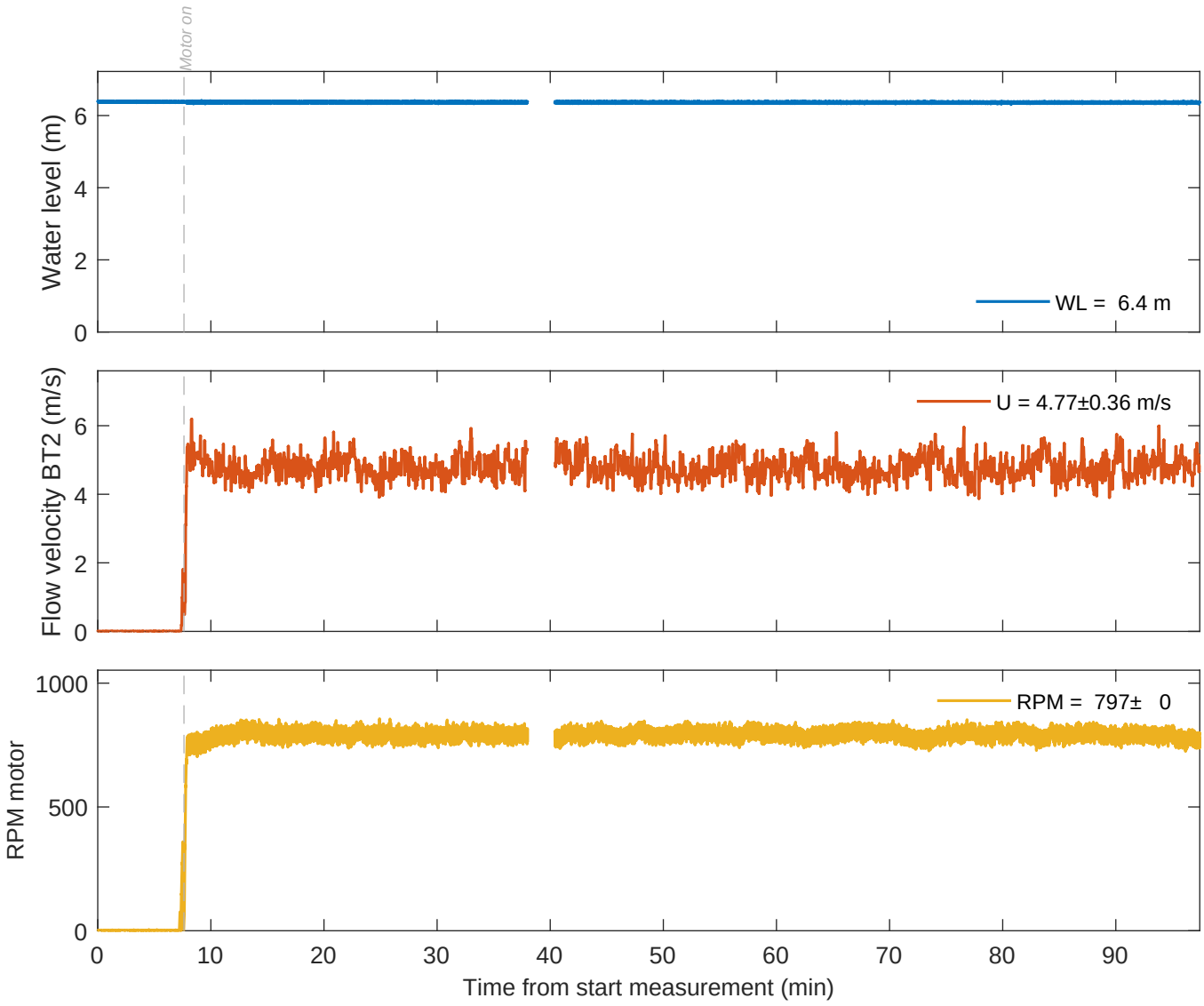
Water level, flow velocity BT2, RPM motor Active thruster: BT2 Δx = 0.8 m, Δy = -4.0 m, UKC = 2.5 m, U_{BT2} = 3.6 m/s	Measurement signals	TKI-SOP
	PIVSOP087	
Deltares	11206641	Fig. C



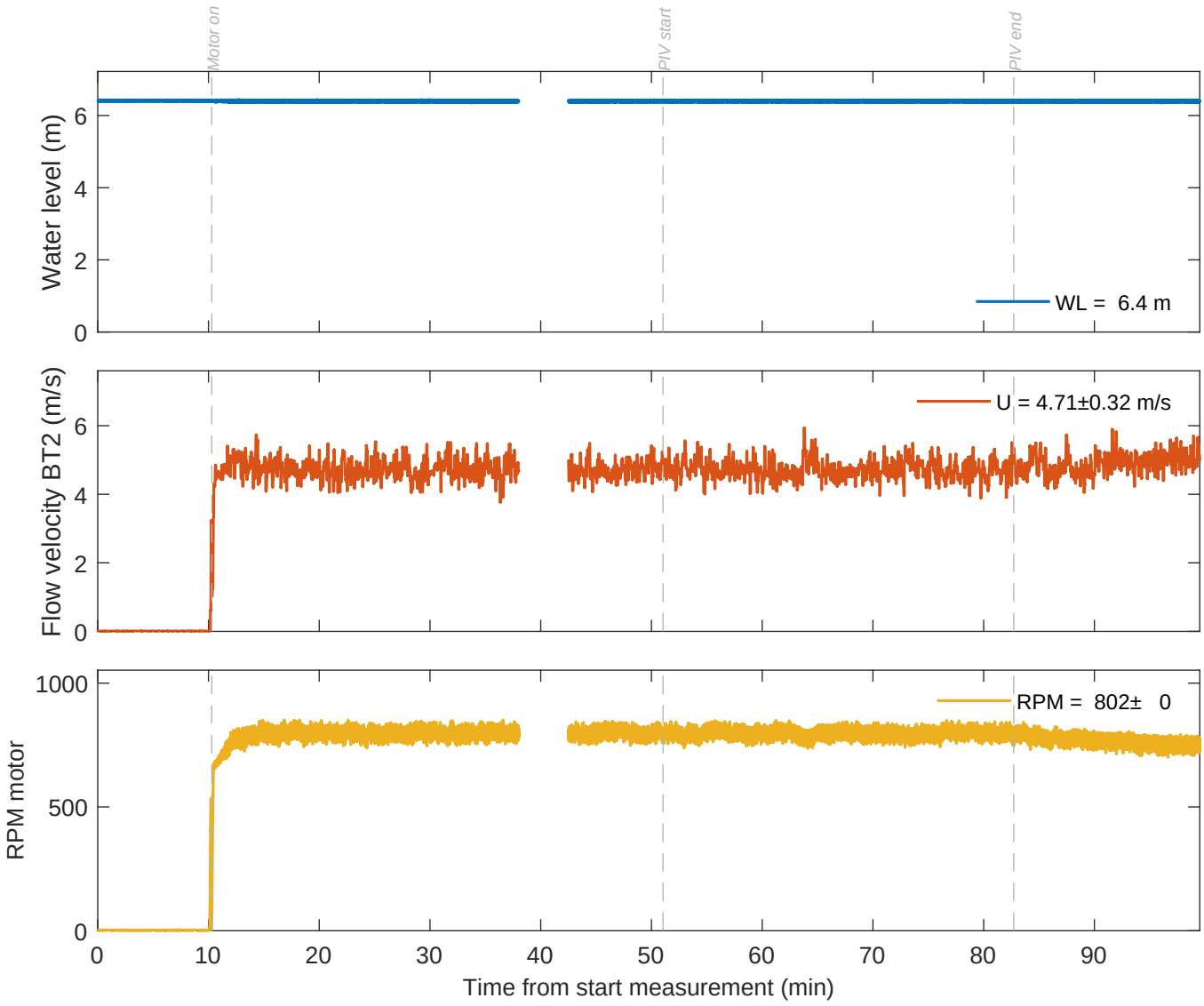
Water level, flow velocity BT2, RPM motor Active thruster: BT2 Δx = 0.8 m, Δy = -4.0 m, UKC = 2.5 m, U_{BT2} = 2.6 m/s	Measurement signals	TKI-SOP
	PIVSOP091	
Deltares	11206641	Fig. C



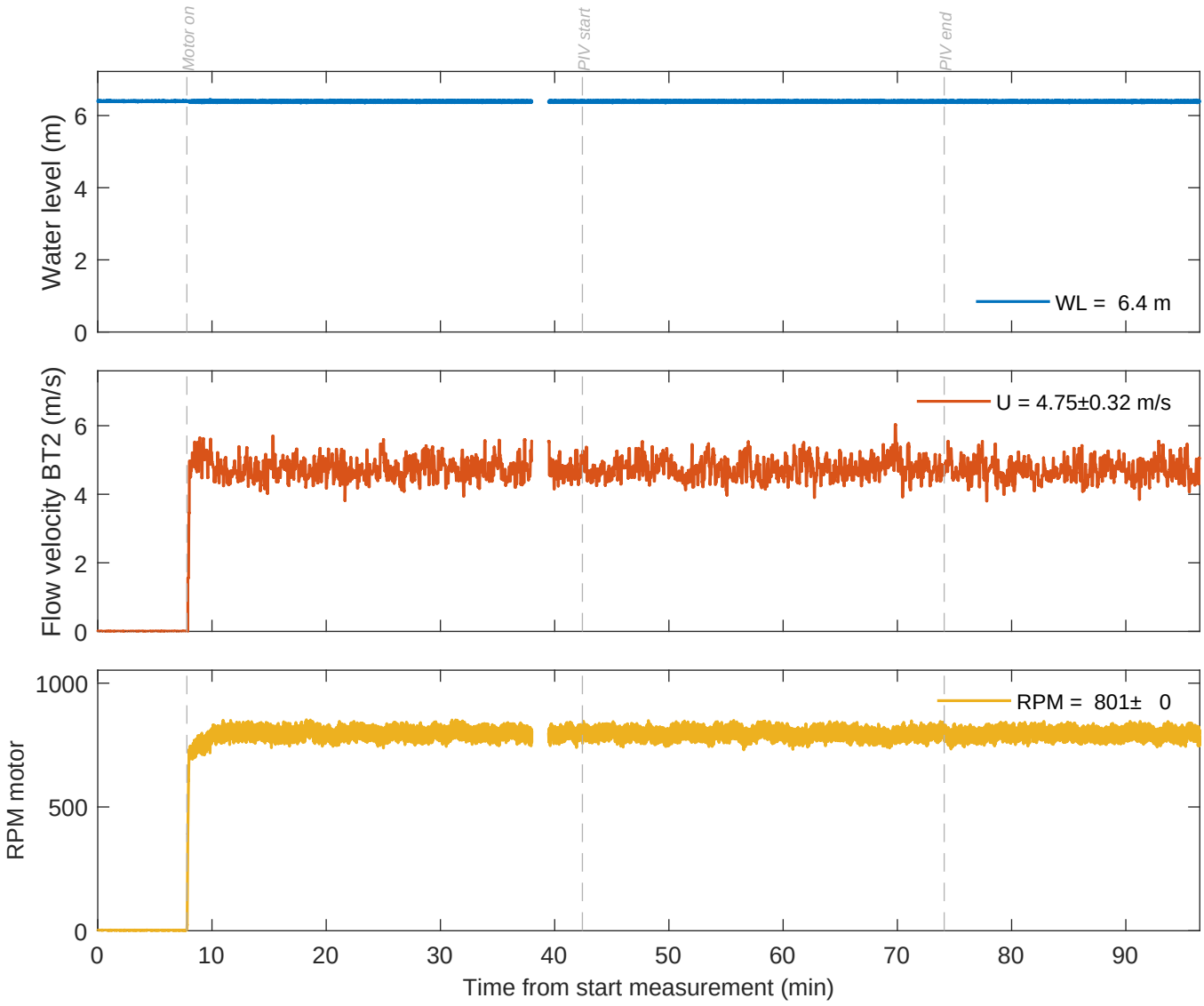
Water level, flow velocity BT2, RPM motor Active thruster: BT2 Δx = 0.8 m, Δy = -4.0 m, UKC = 2.5 m, U_{BT2} = 4.7 m/s	Measurement signals	TKI-SOP
	PIVSOP093	
Deltares	11206641	Fig. C



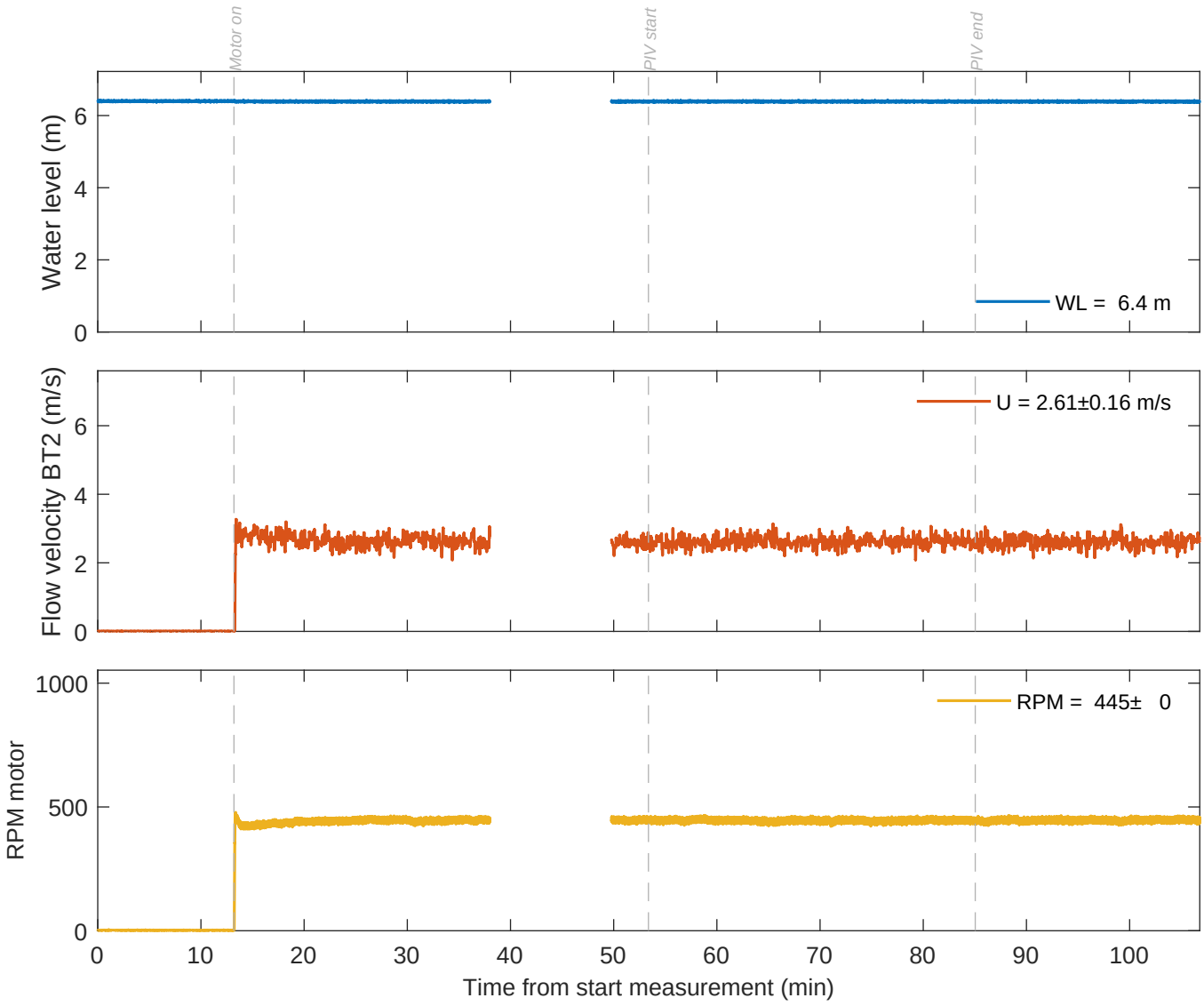
Water level, flow velocity BT2, RPM motor Active thruster: BT2 Δx = 0.8 m, Δy = -2.0 m, UKC = 2.4 m, U_{BT2} = 4.8 m/s	Measurement signals	TKI-SOP
	PIVSOP096	
Deltares	11206641	Fig. C



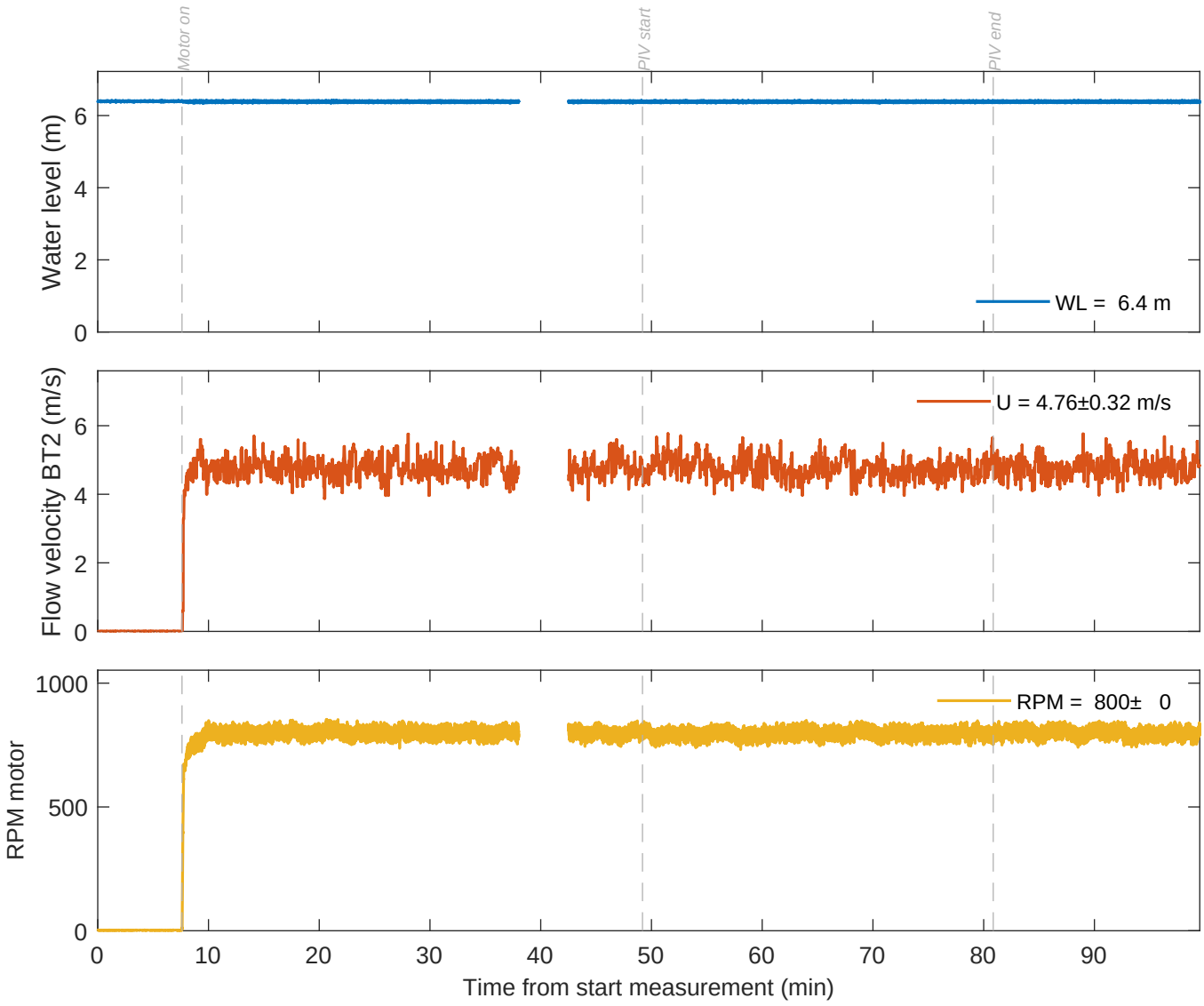
Water level, flow velocity BT2, RPM motor Active thruster: BT2 Δx = 0.8 m, Δy = 2.0 m, UKC = 2.4 m, U_{BT2} = 4.7 m/s	Measurement signals	TKI-SOP
	PIVSOP099	
Deltares	11206641	Fig. C



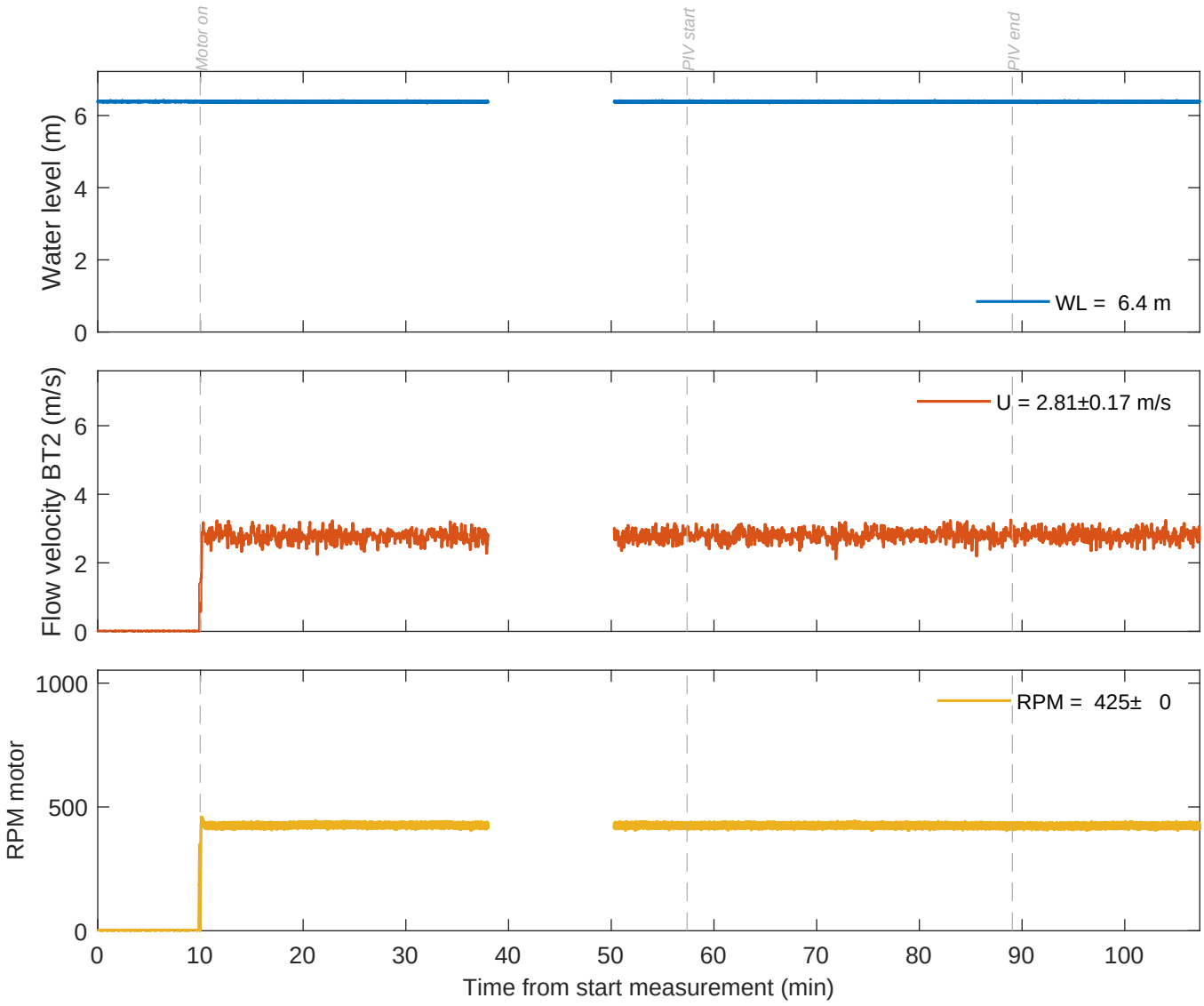
Water level, flow velocity BT2, RPM motor Active thruster: BT2 Δx = 0.8 m, Δy = 3.5 m, UKC = 2.4 m, U_{BT2} = 4.7 m/s	Measurement signals	TKI-SOP
	PIVSOP102	
Deltares	11206641	Fig. C



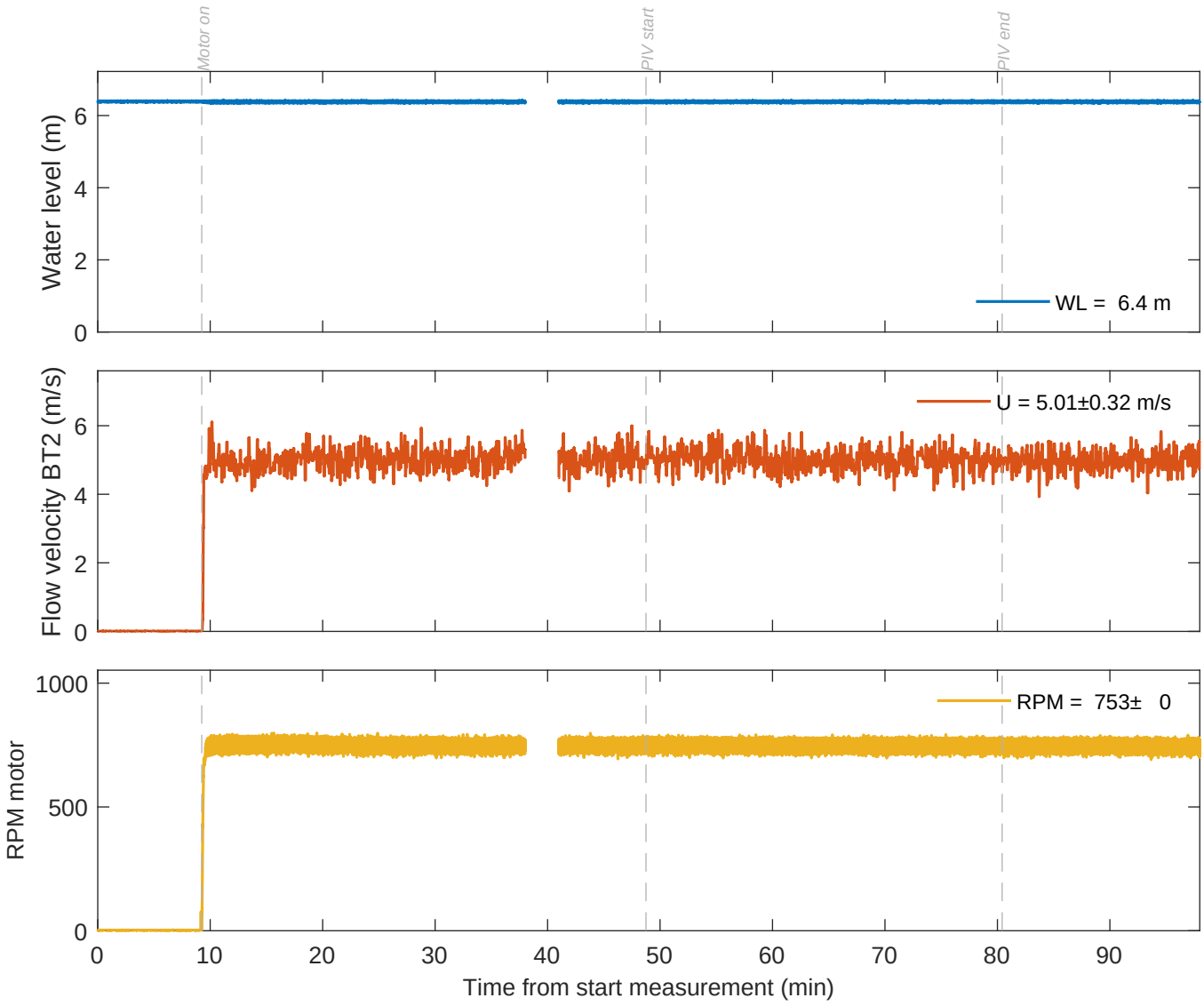
Water level, flow velocity BT2, RPM motor Active thruster: BT2 Δx = 0.8 m, Δy = 0.0 m, UKC = 2.4 m, U_{BT2} = 2.6 m/s	Measurement signals	TKI-SOP
	PIVSOP105	
Deltares	11206641	Fig. C



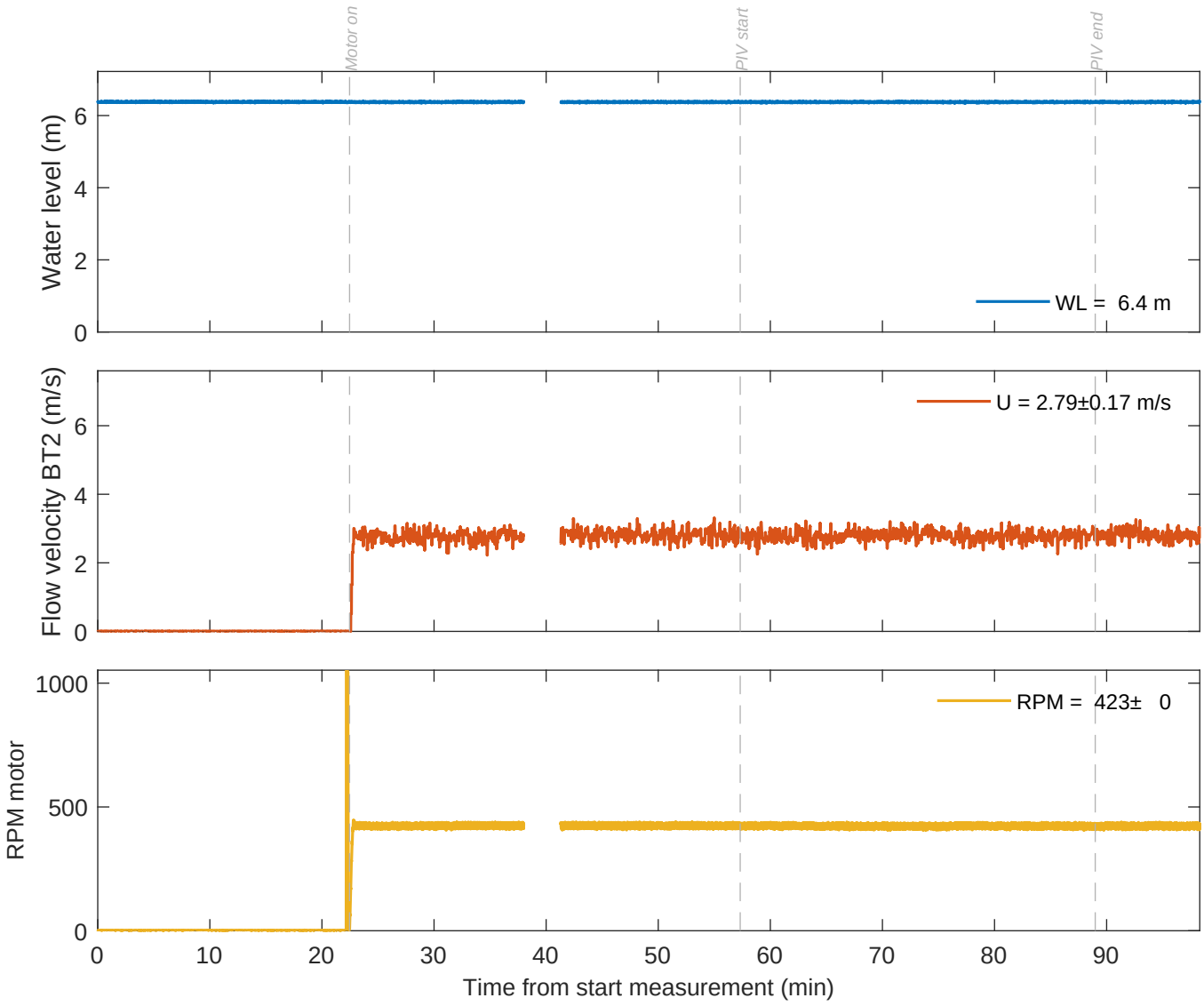
Water level, flow velocity BT2, RPM motor Active thruster: BT2 Δx = 0.8 m, Δy = 0.0 m, UKC = 2.4 m, U_{BT2} = 4.8 m/s	Measurement signals	TKI-SOP
	PIVSOP107	
Deltares	11206641	Fig. C



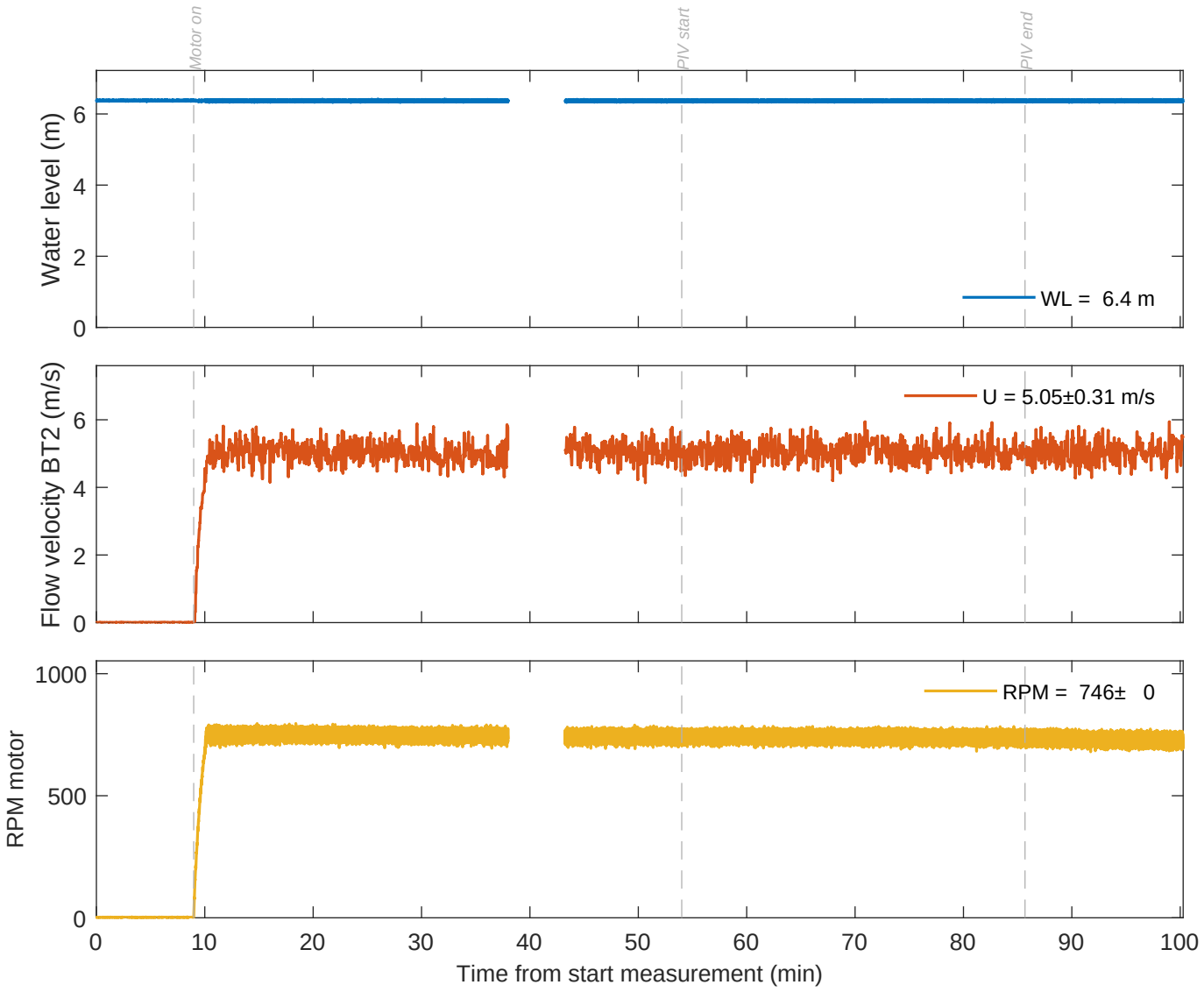
Water level, flow velocity BT2, RPM motor Active thruster: BT2 Δx = 5.0 m, Δy = 0.0 m, UKC = 2.4 m, U_{BT2} = 2.8 m/s	Measurement signals	TKI-SOP
	PIVSOP110	
Deltares	11206641	Fig. C



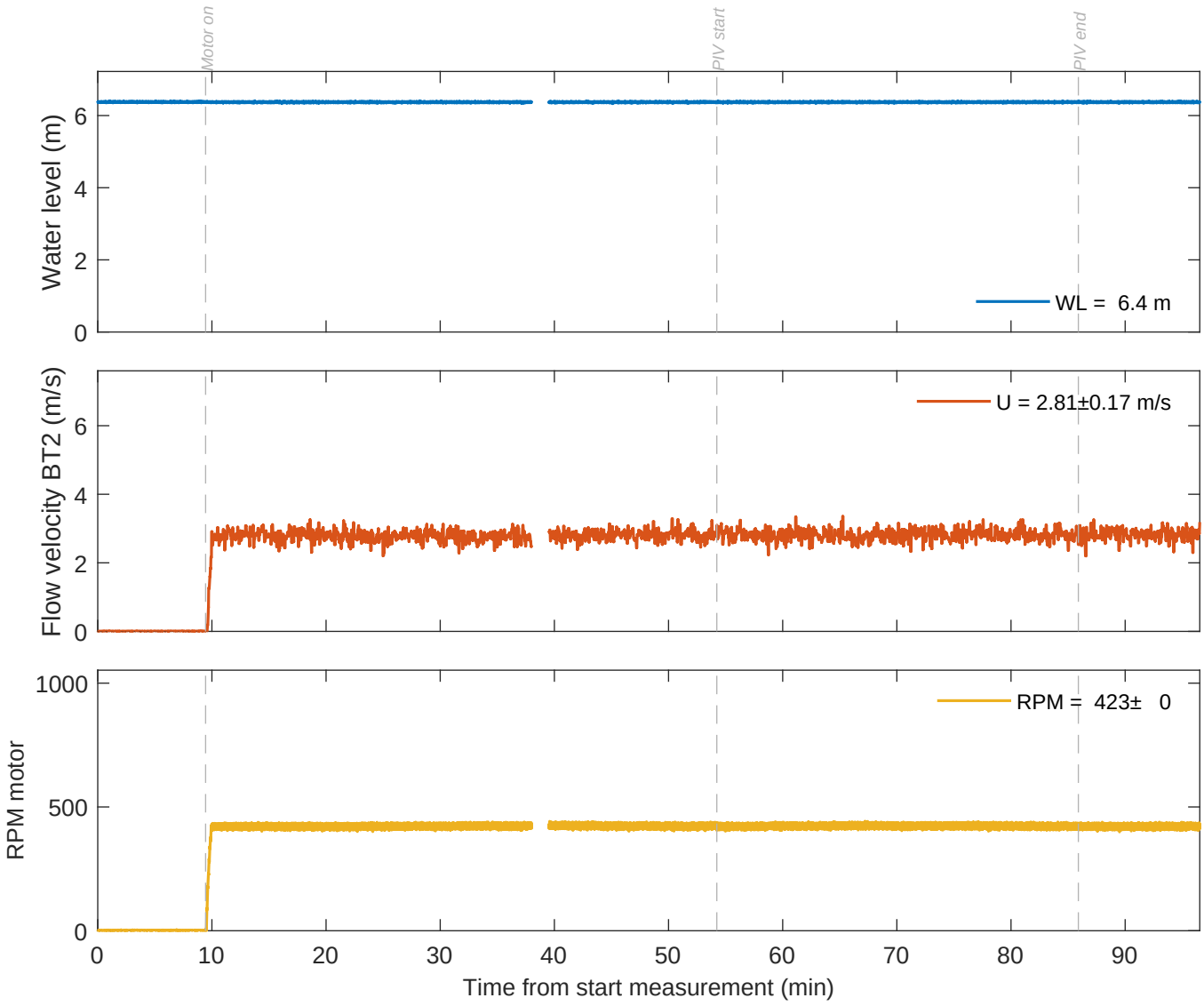
Water level, flow velocity BT2, RPM motor Active thruster: BT2 Δx = 5.0 m, Δy = 0.0 m, UKC = 2.4 m, U_{BT2} = 5.0 m/s	Measurement signals	TKI-SOP
	PIVSOP112	
Deltares	11206641	Fig. C



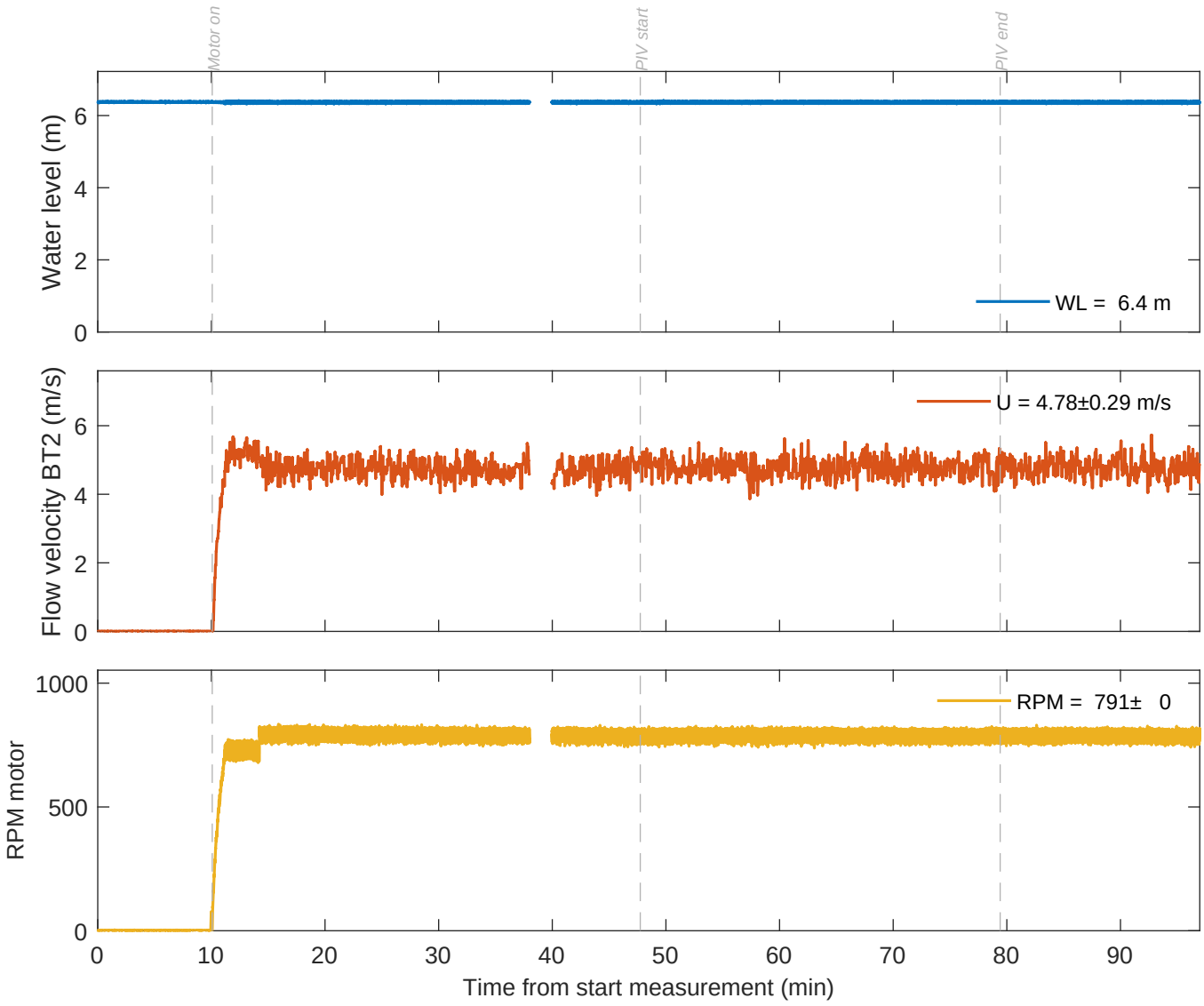
Water level, flow velocity BT2, RPM motor Active thruster: BT2 Δx = 5.0 m, Δy = -2.0 m, UKC = 2.4 m, U_{BT2} = 2.8 m/s	Measurement signals	TKI-SOP
	PIVSOP115	
Deltares	11206641	Fig. C



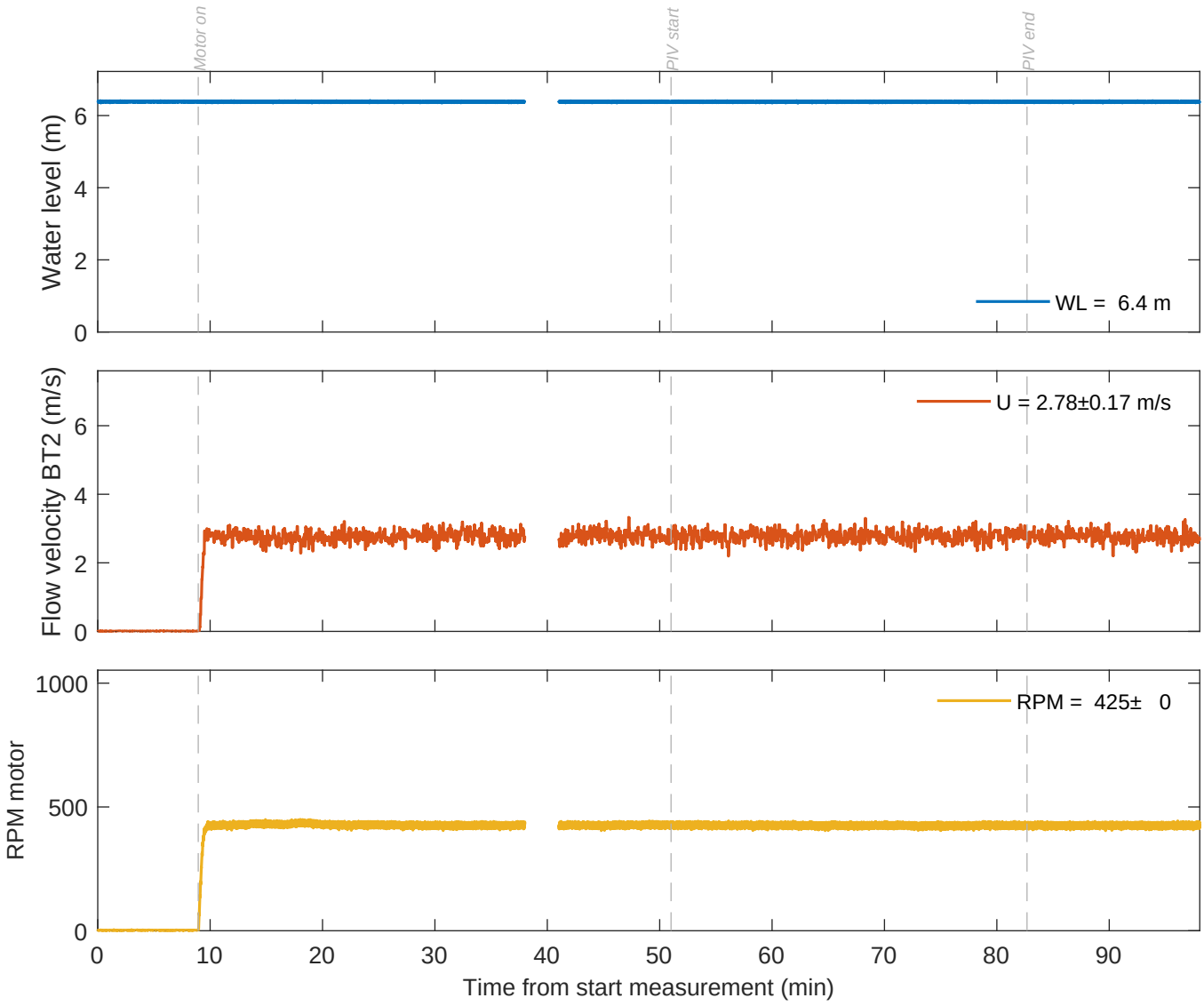
Water level, flow velocity BT2, RPM motor Active thruster: BT2 Δx = 5.0 m, Δy = -2.0 m, UKC = 2.4 m, U_{BT2} = 5.1 m/s	Measurement signals	TKI-SOP
	PIVSOP117	
Deltares	11206641	Fig. C



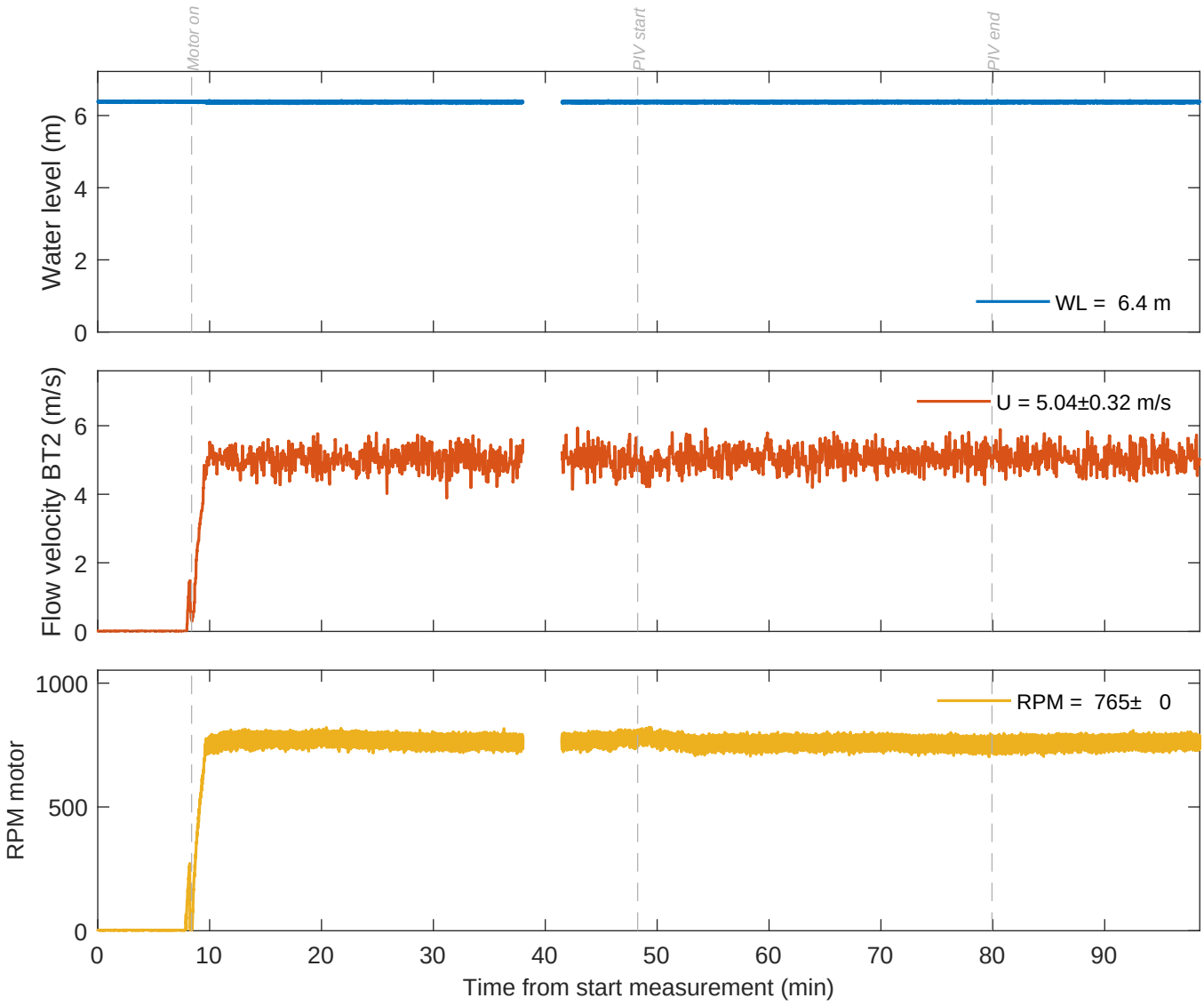
Water level, flow velocity BT2, RPM motor Active thruster: BT2 Δx = 5.0 m, Δy = 2.0 m, UKC = 2.4 m, U_{BT2} = 2.8 m/s	Measurement signals	TKI-SOP
	PIVSOP119	
Deltares	11206641	Fig. C



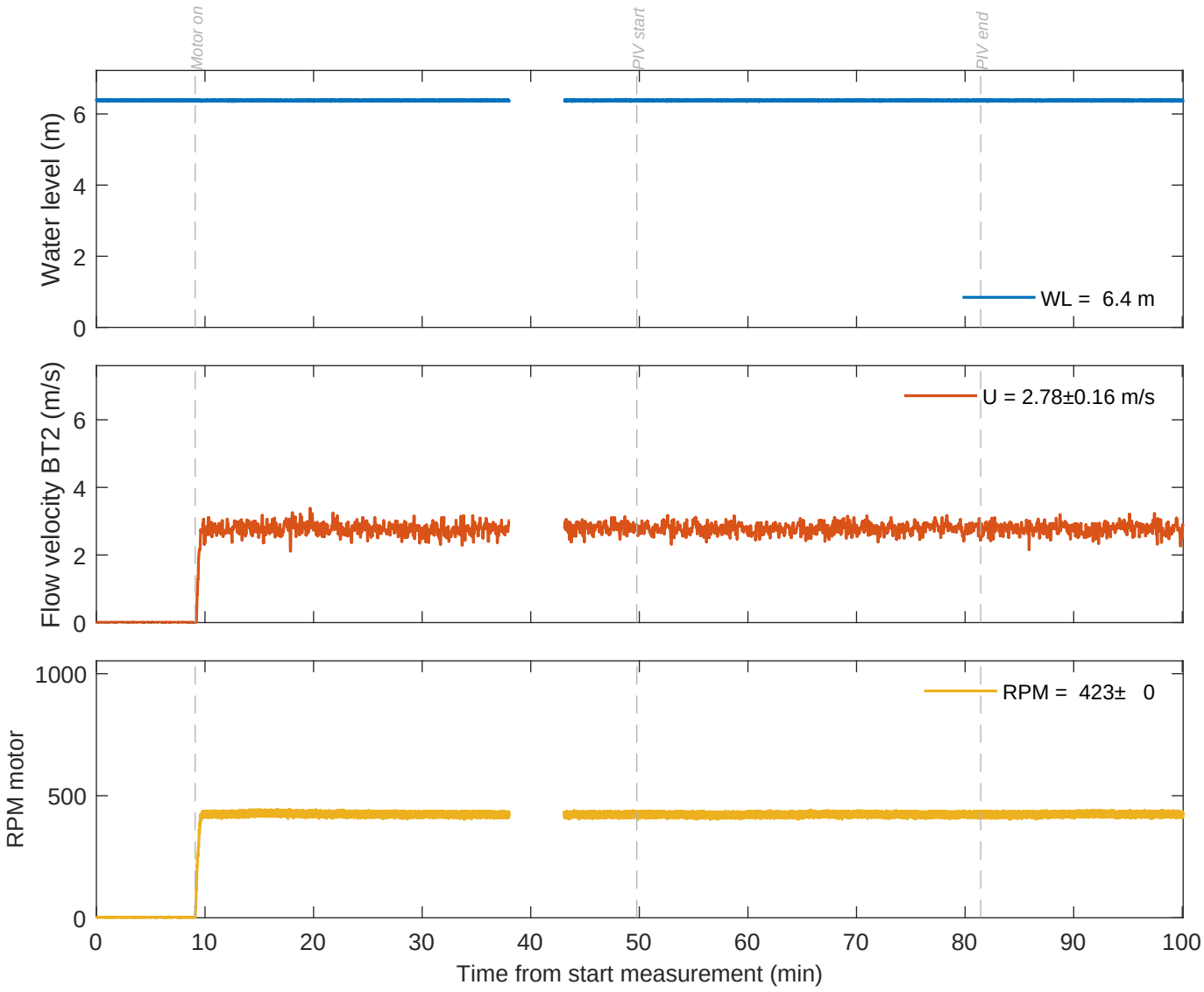
Water level, flow velocity BT2, RPM motor Active thruster: BT2 Δx = 5.0 m, Δy = 2.0 m, UKC = 2.4 m, U_{BT2} = 4.8 m/s	Measurement signals	TKI-SOP
	PIVSOP121	
Deltares	11206641	Fig. C



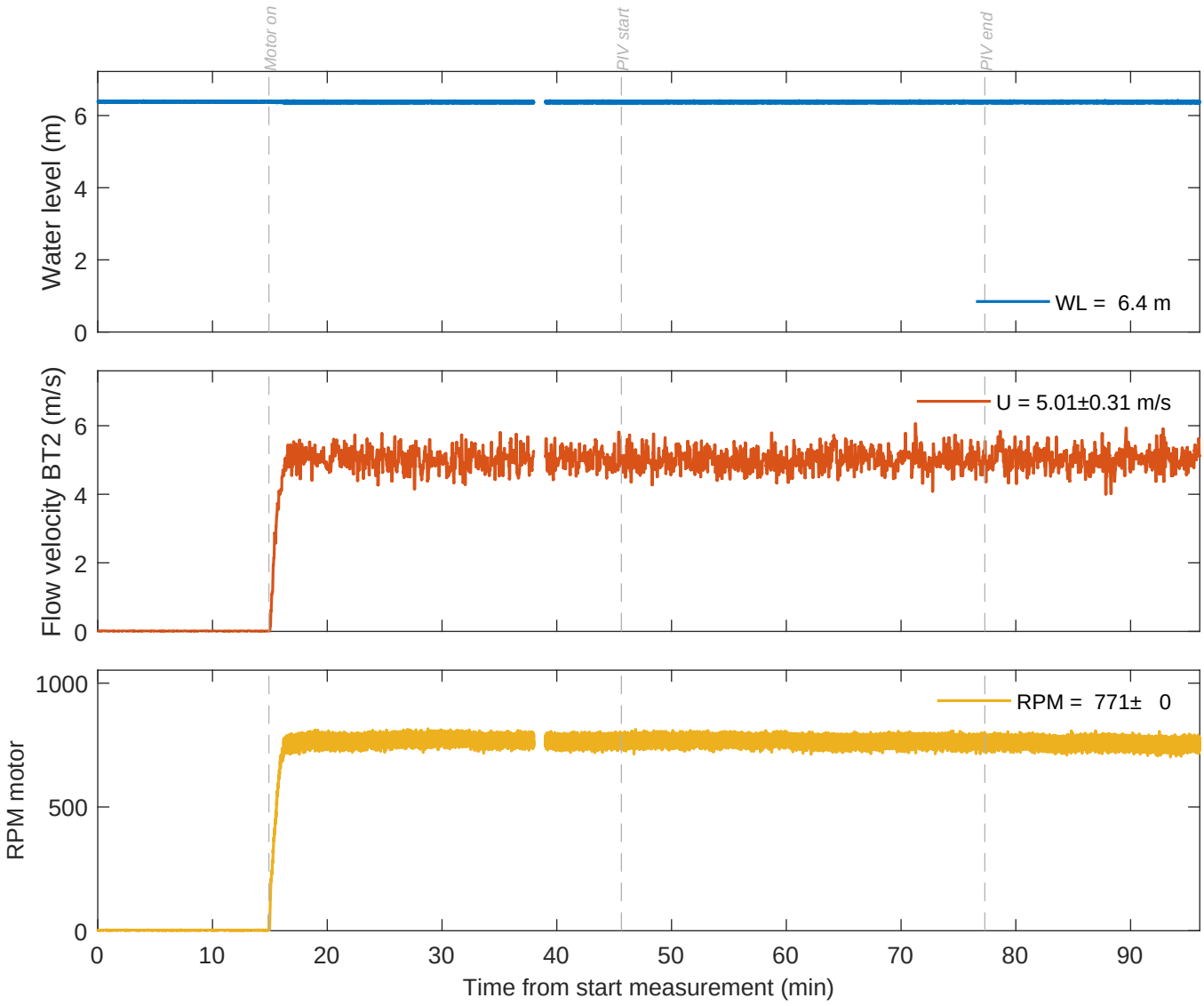
Water level, flow velocity BT2, RPM motor Active thruster: BT2 Δx = 3.0 m, Δy = 2.0 m, UKC = 2.4 m, U_{BT2} = 2.8 m/s	Measurement signals	TKI-SOP
	PIVSOP124	
Deltares	11206641	Fig. C



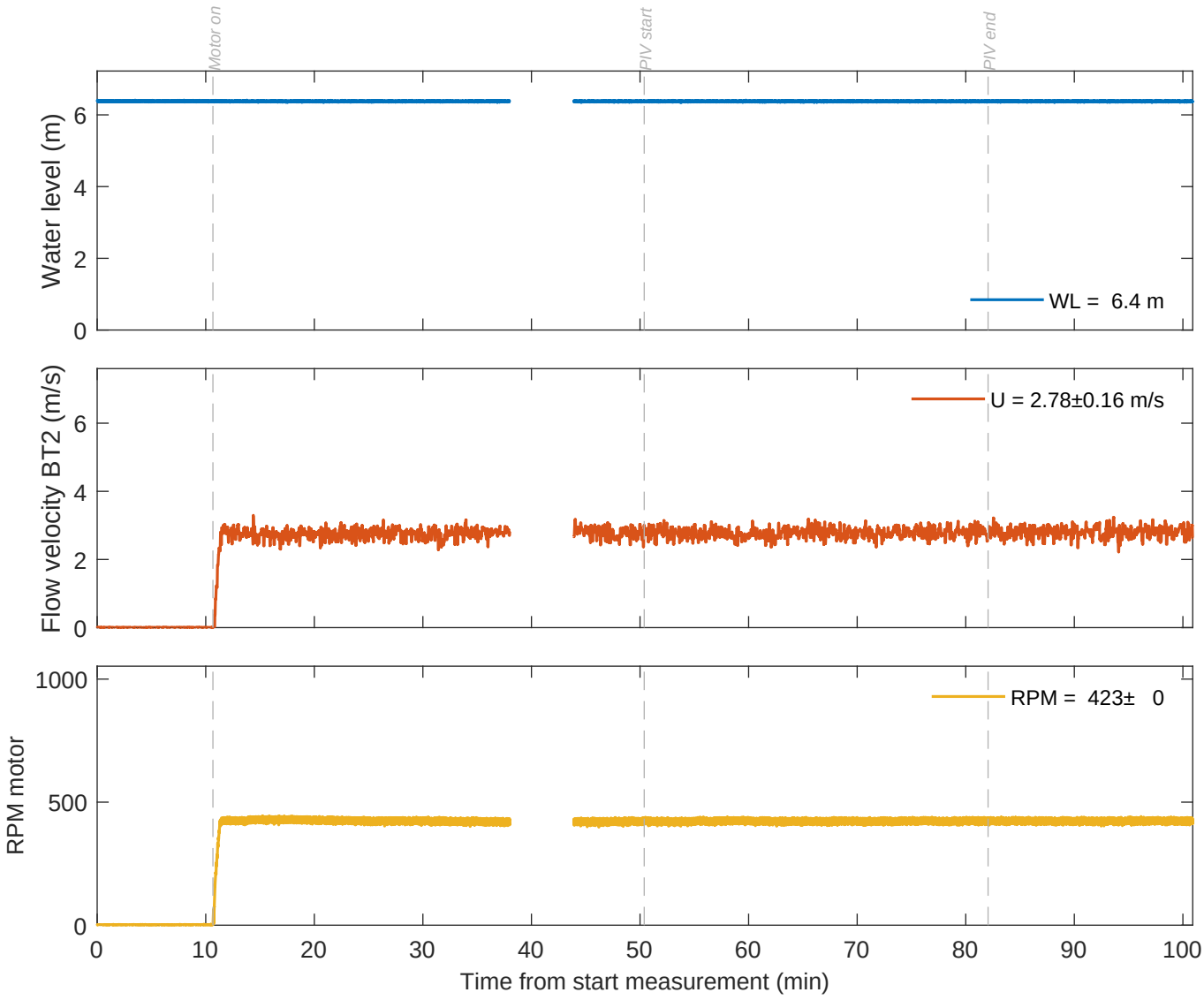
Water level, flow velocity BT2, RPM motor Active thruster: BT2 Δx = 3.0 m, Δy = 2.0 m, UKC = 2.4 m, U_{BT2} = 5.0 m/s	Measurement signals	TKI-SOP
	PIVSOP126	
Deltares	11206641	Fig. C



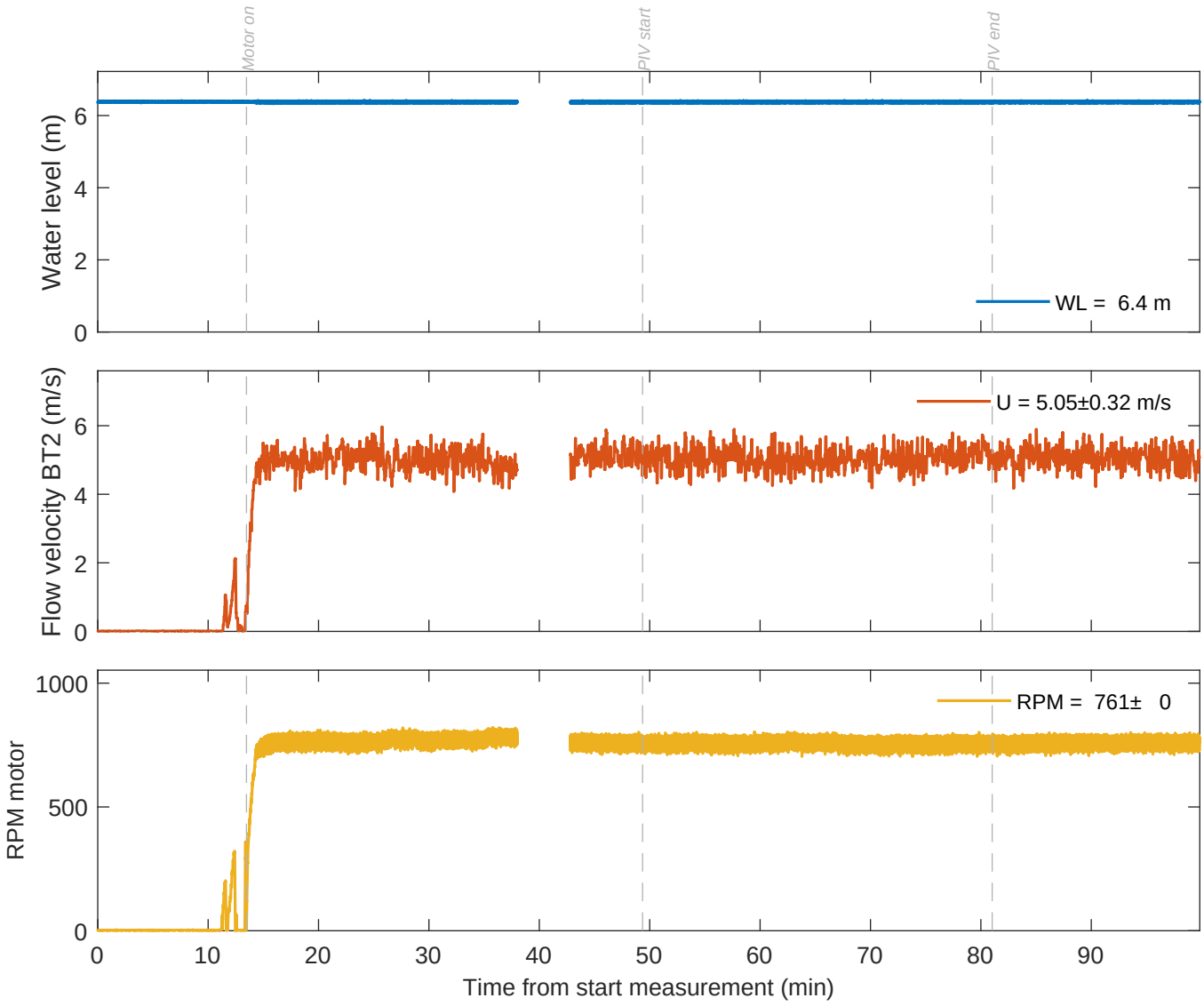
Water level, flow velocity BT2, RPM motor Active thruster: BT2 Δx = 3.0 m, Δy = 0.0 m, UKC = 2.4 m, U_{BT2} = 2.8 m/s	Measurement signals	TKI-SOP
	PIVSOP131	
Deltares	11206641	Fig. C



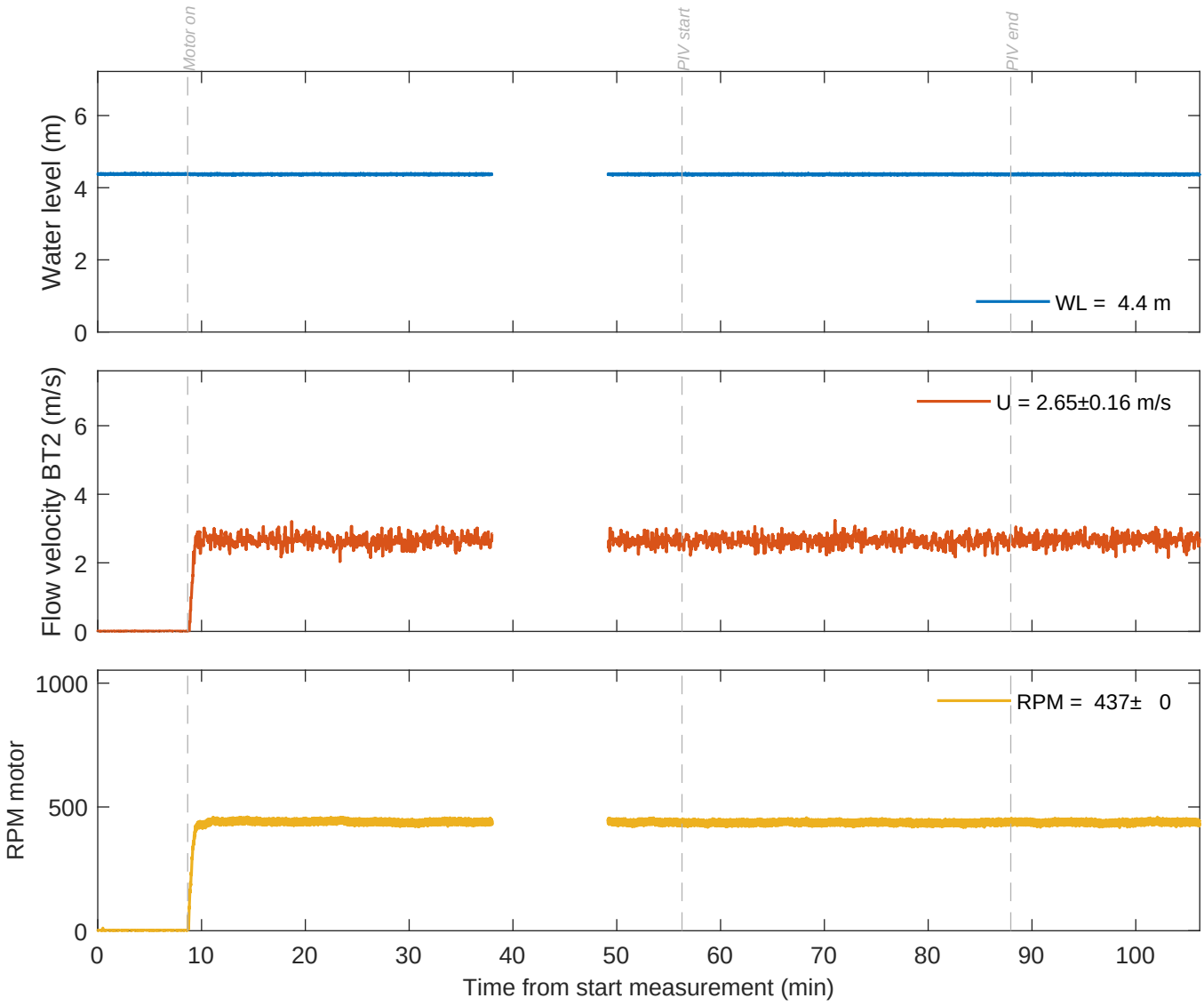
Water level, flow velocity BT2, RPM motor Active thruster: BT2 Δx = 3.0 m, Δy = 0.0 m, UKC = 2.4 m, U_{BT2} = 5.0 m/s	Measurement signals	TKI-SOP
	PIVSOP133	
Deltares	11206641	Fig. C



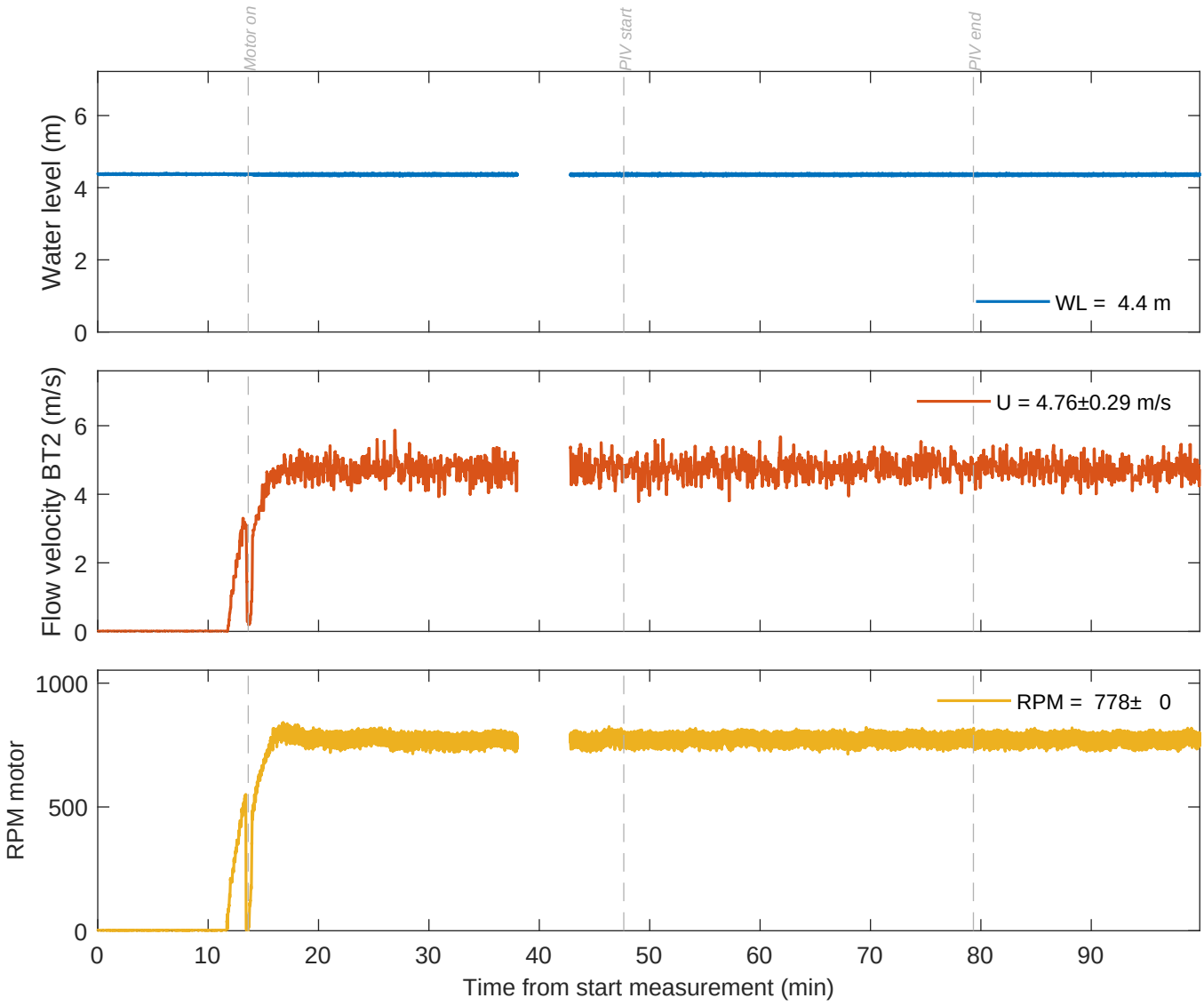
Water level, flow velocity BT2, RPM motor Active thruster: BT2 Δx = 3.0 m, Δy = -2.0 m, UKC = 2.5 m, U_{BT2} = 2.8 m/s	Measurement signals	TKI-SOP
	PIVSOP135	
Deltares	11206641	Fig. C



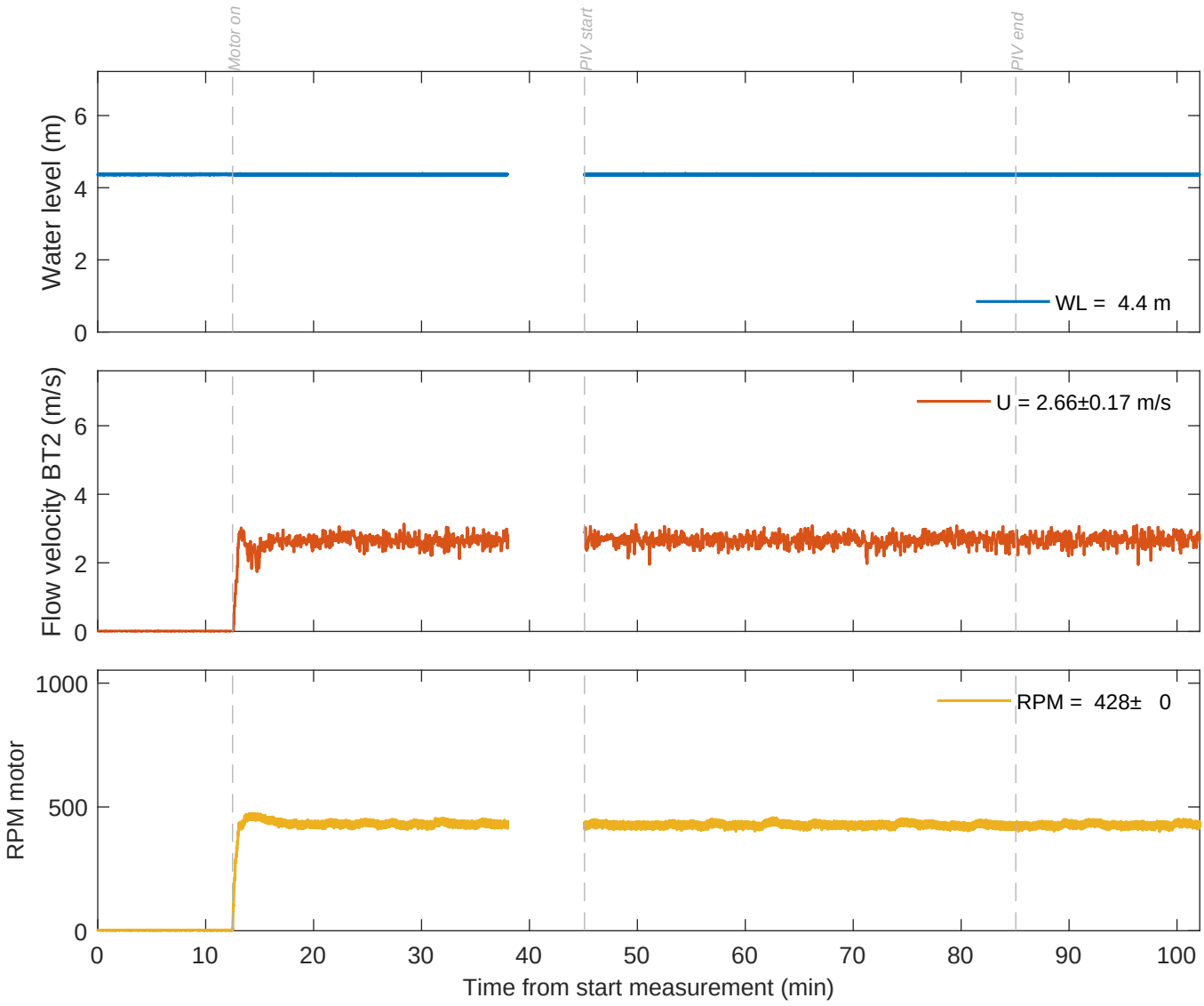
Water level, flow velocity BT2, RPM motor Active thruster: BT2 Δx = 3.0 m, Δy = -2.0 m, UKC = 2.5 m, U_{BT2} = 5.0 m/s	Measurement signals	TKI-SOP
	PIVSOP137	
Deltares	11206641	Fig. C



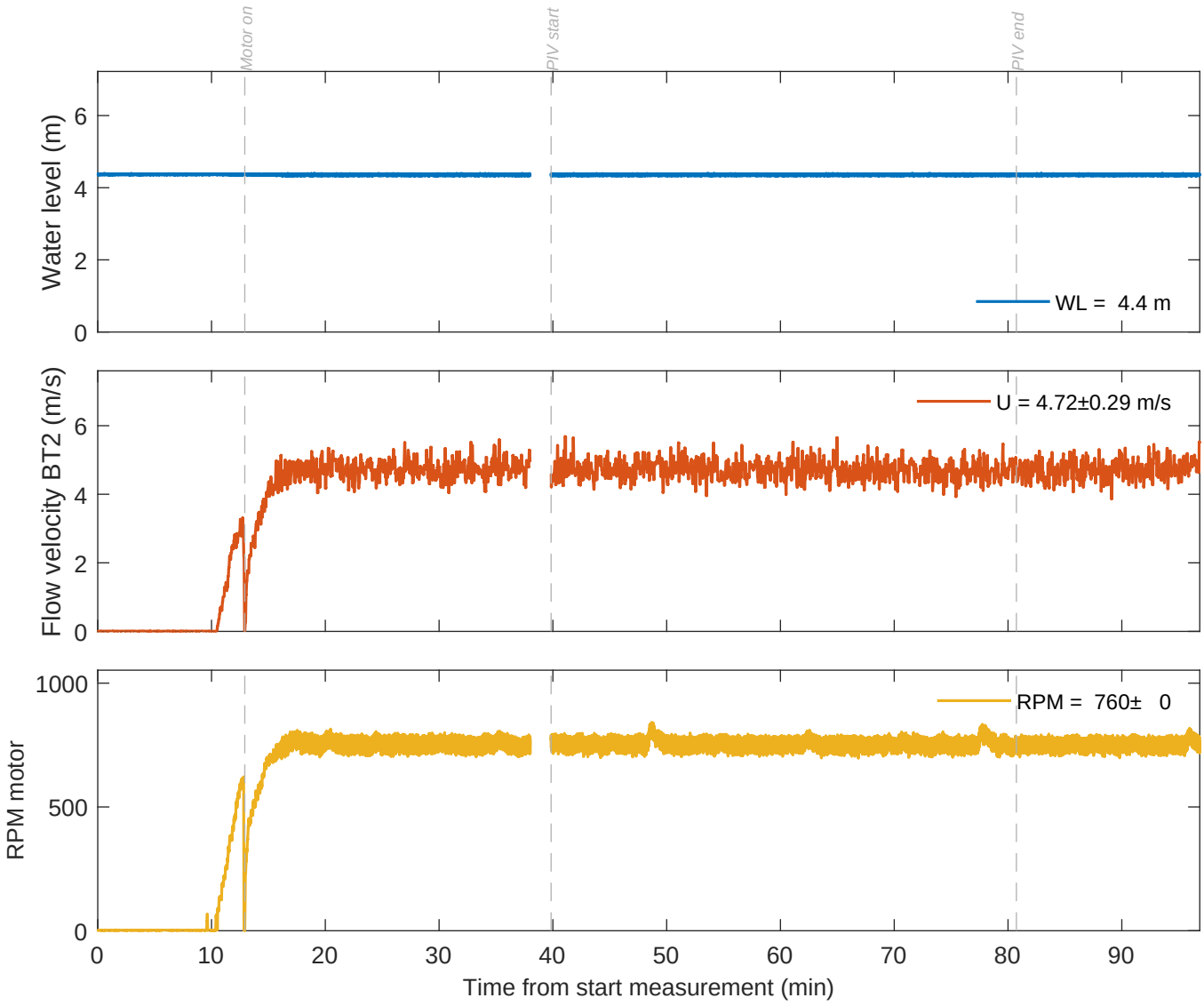
Water level, flow velocity BT2, RPM motor Active thruster: BT2 Δx = 3.0 m, Δy = 0.0 m, UKC = 0.4 m, U_{BT2} = 2.6 m/s	Measurement signals	TKI-SOP
	PIVSOP140	
Deltares	11206641	Fig. C



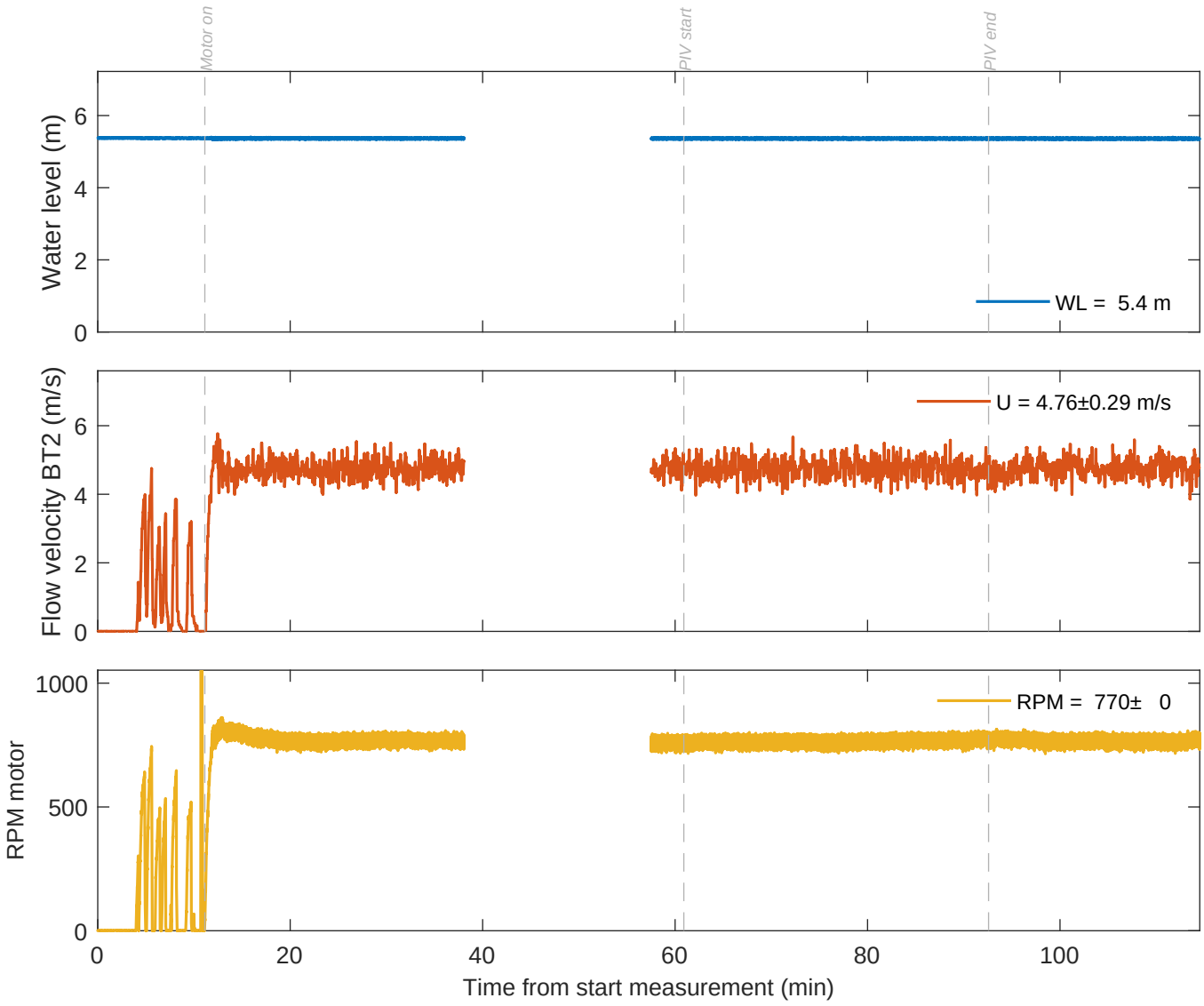
Water level, flow velocity BT2, RPM motor Active thruster: BT2 Δx = 3.0 m, Δy = 0.0 m, UKC = 0.4 m, U_{BT2} = 4.8 m/s	Measurement signals	TKI-SOP
	PIVSOP142	
Deltares	11206641	Fig. C



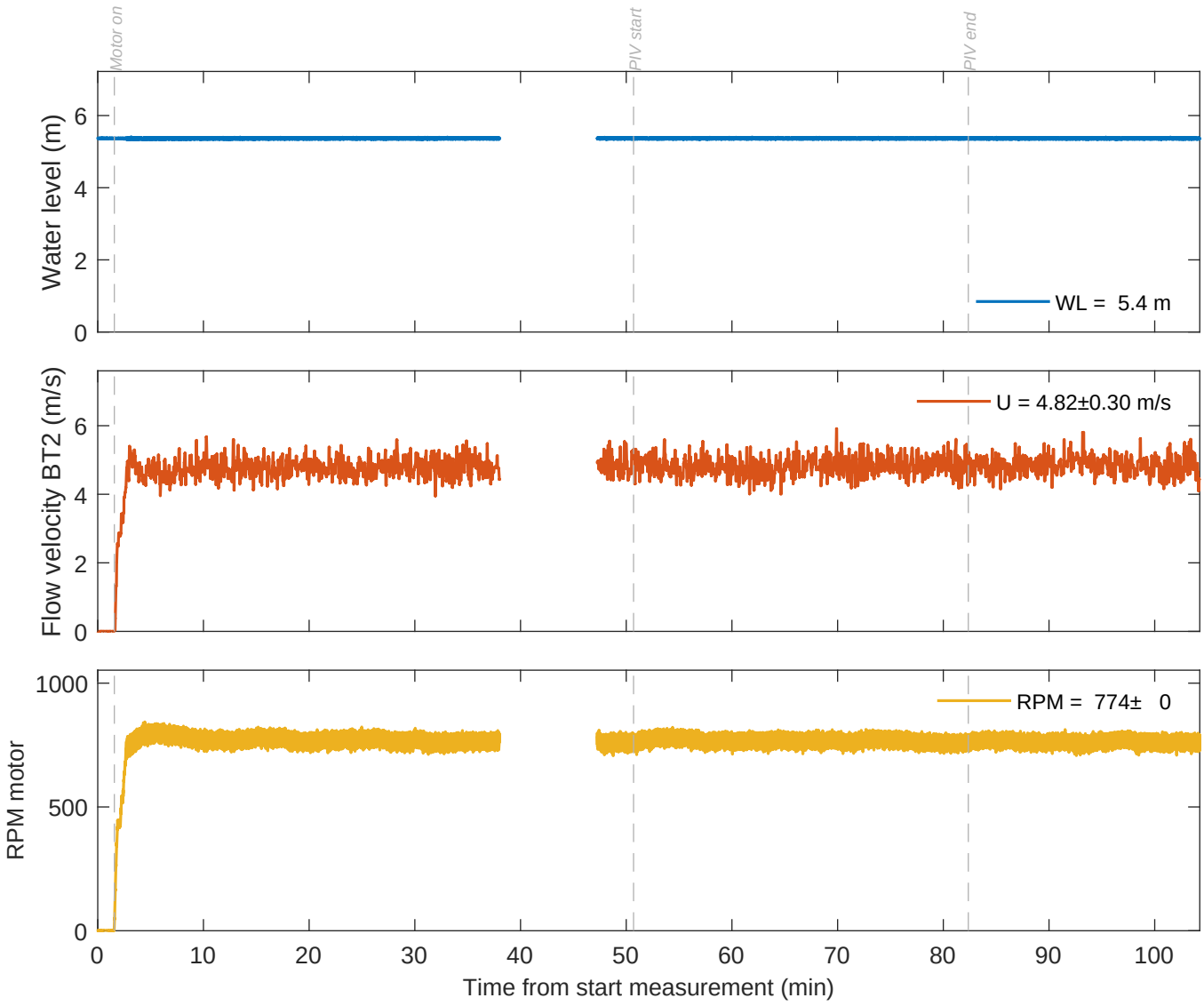
Water level, flow velocity BT2, RPM motor Active thruster: BT2 Δx = 0.8 m, Δy = 0.0 m, UKC = 0.4 m, U_{BT2} = 2.7 m/s	Measurement signals	TKI-SOP
	PIVSOP144	
Deltares	11206641	Fig. C



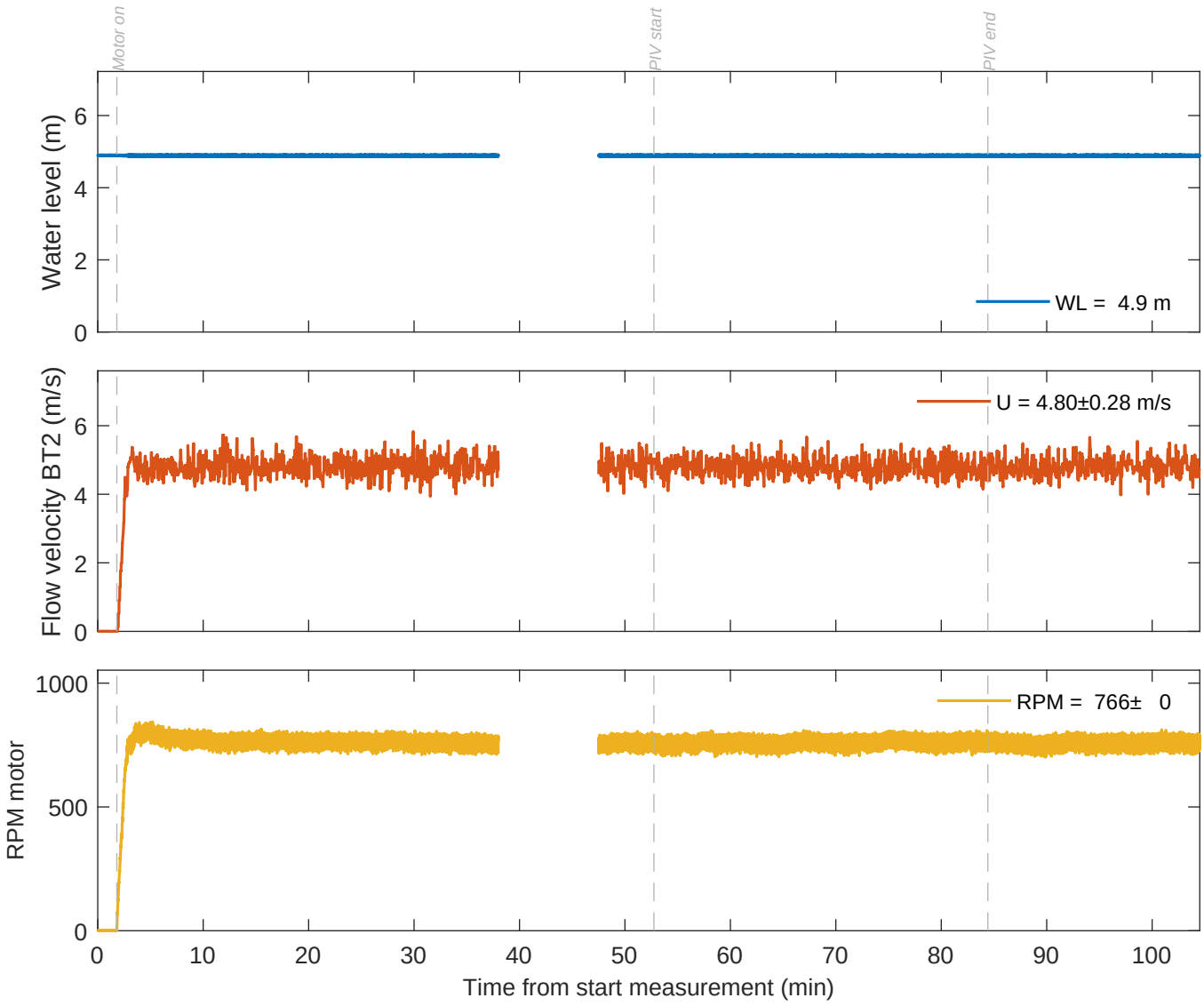
Water level, flow velocity BT2, RPM motor Active thruster: BT2 Δx = 0.8 m, Δy = 0.0 m, UKC = 0.4 m, U_{BT2} = 4.7 m/s	Measurement signals	TKI-SOP
	PIVSOP146	
Deltares	11206641	Fig. C



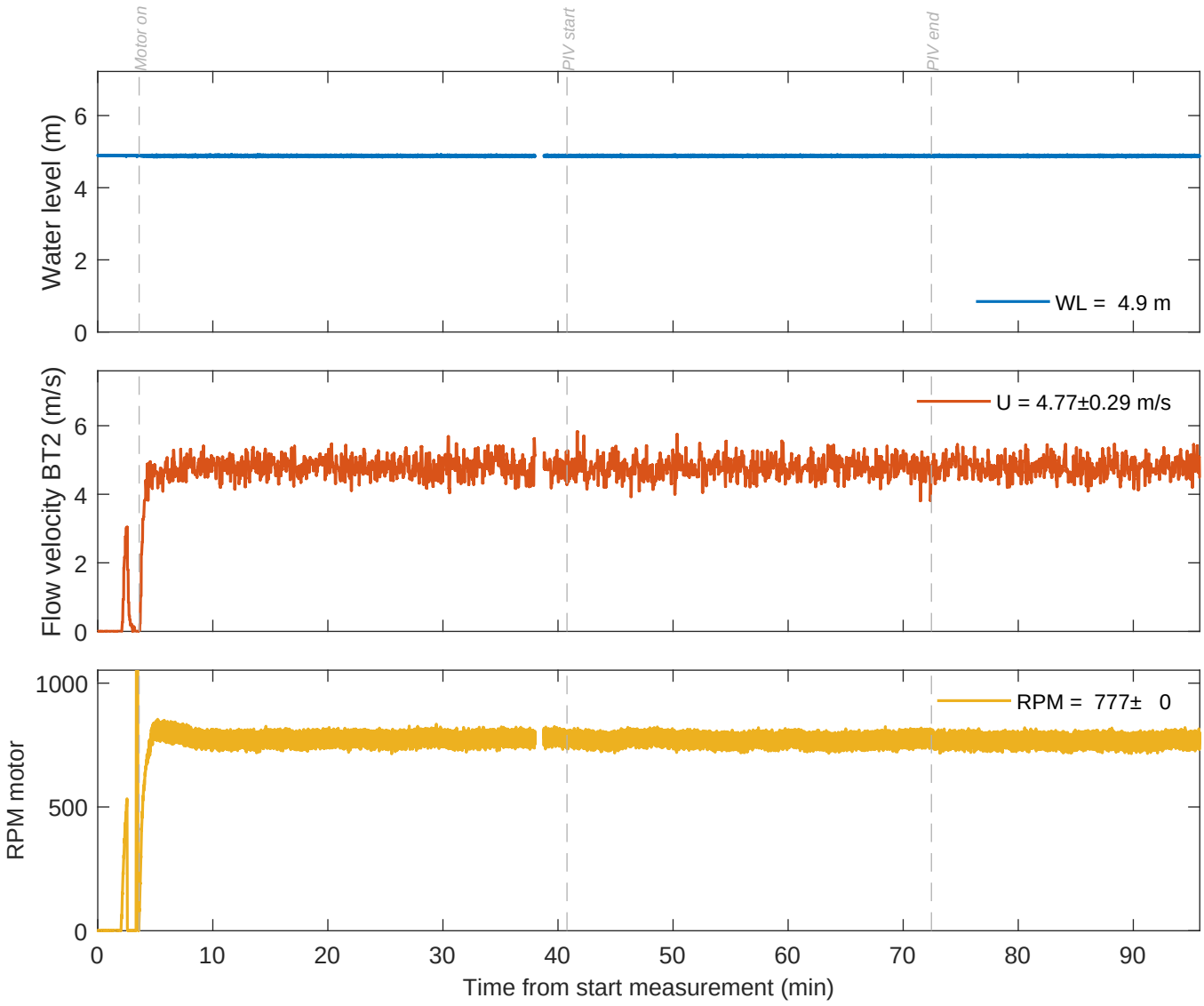
Water level, flow velocity BT2, RPM motor Active thruster: BT2 Δx = 0.8 m, Δy = 0.0 m, UKC = 1.4 m, U_{BT2} = 4.8 m/s	Measurement signals	TKI-SOP
	PIVSOP150	
Deltares	11206641	Fig. C



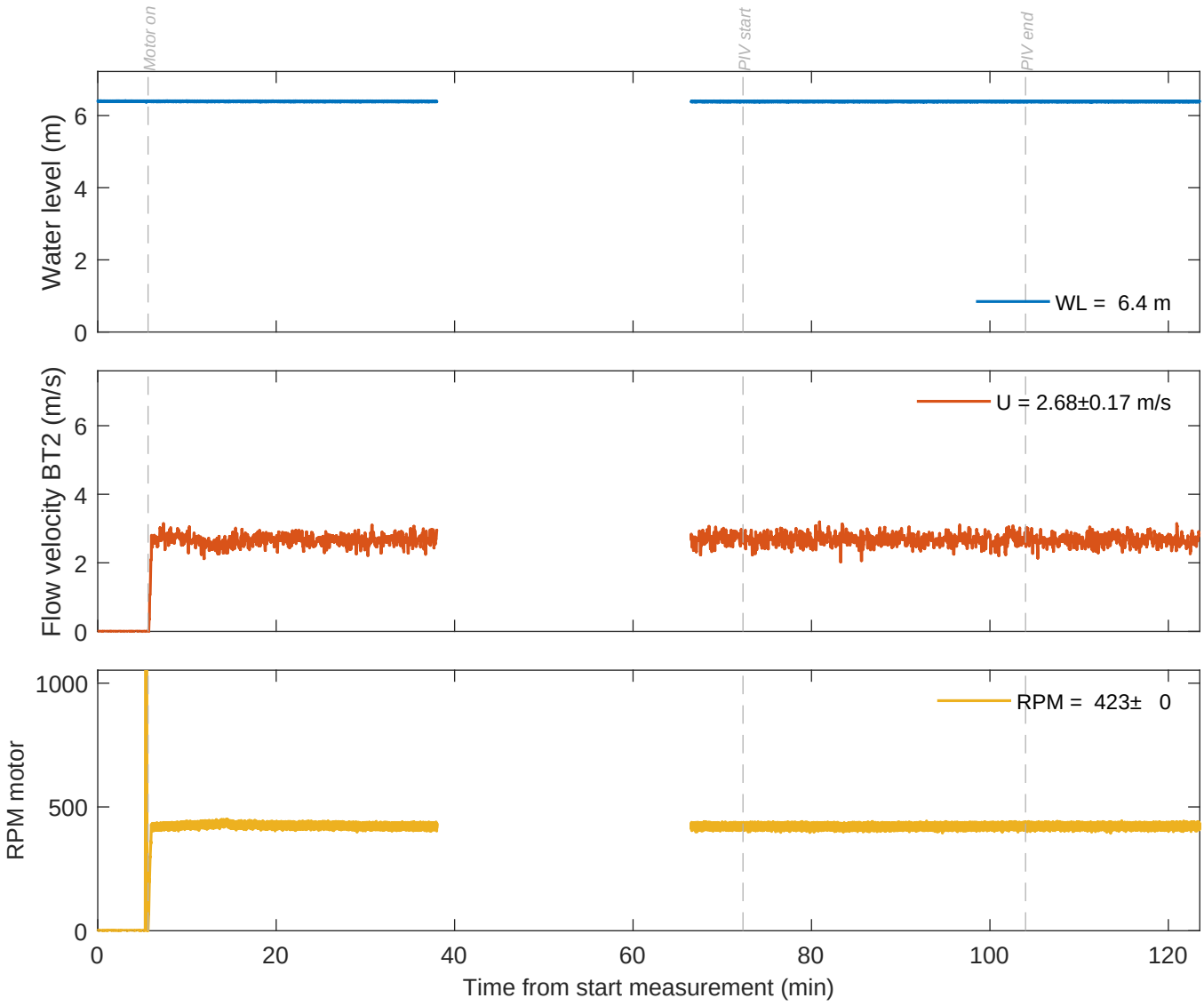
Water level, flow velocity BT2, RPM motor Active thruster: BT2 Δx = 3.0 m, Δy = 0.0 m, UKC = 1.4 m, U_{BT2} = 4.8 m/s	Measurement signals	TKI-SOP
	PIVSOP154	
Deltares	11206641	Fig. C



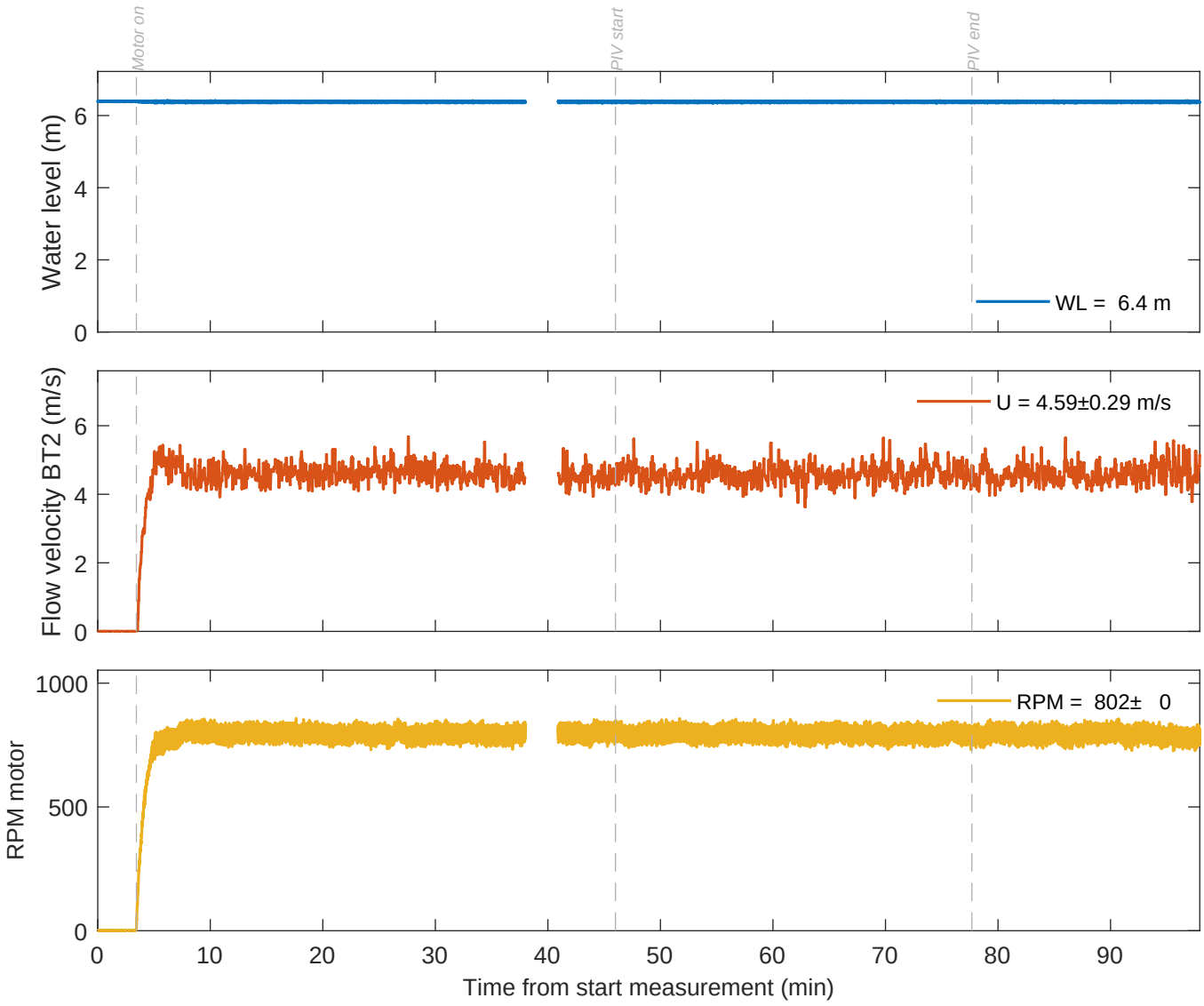
Water level, flow velocity BT2, RPM motor Active thruster: BT2 Δx = 3.0 m, Δy = 0.0 m, UKC = 0.9 m, U_{BT2} = 4.8 m/s	Measurement signals	TKI-SOP
	PIVSOP158	
Deltares	11206641	Fig. C



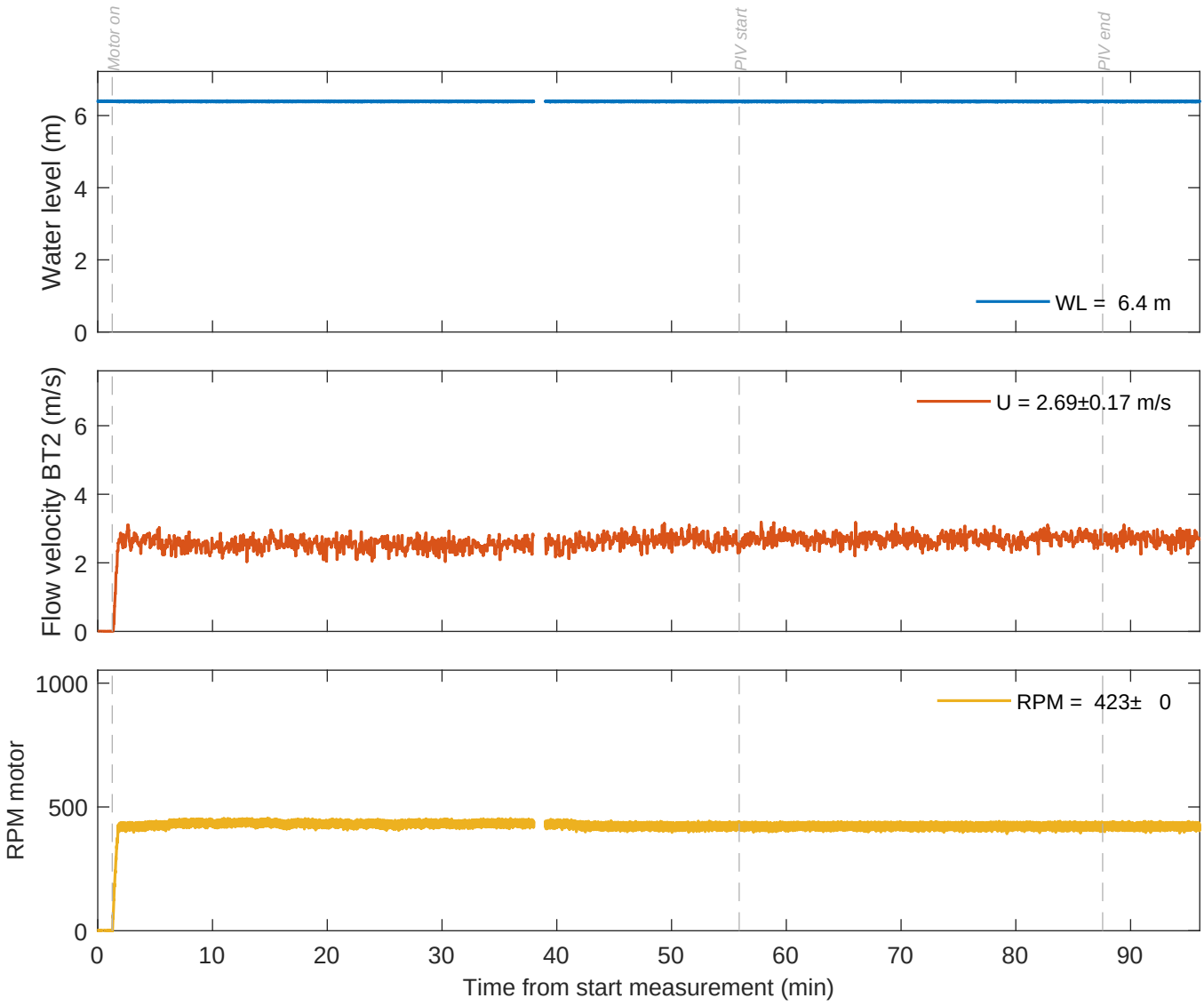
Water level, flow velocity BT2, RPM motor Active thruster: BT2 Δx = 0.8 m, Δy = 0.0 m, UKC = 1.0 m, U_{BT2} = 4.8 m/s	Measurement signals	TKI-SOP
	PIVSOP162	
Deltares	11206641	Fig. C



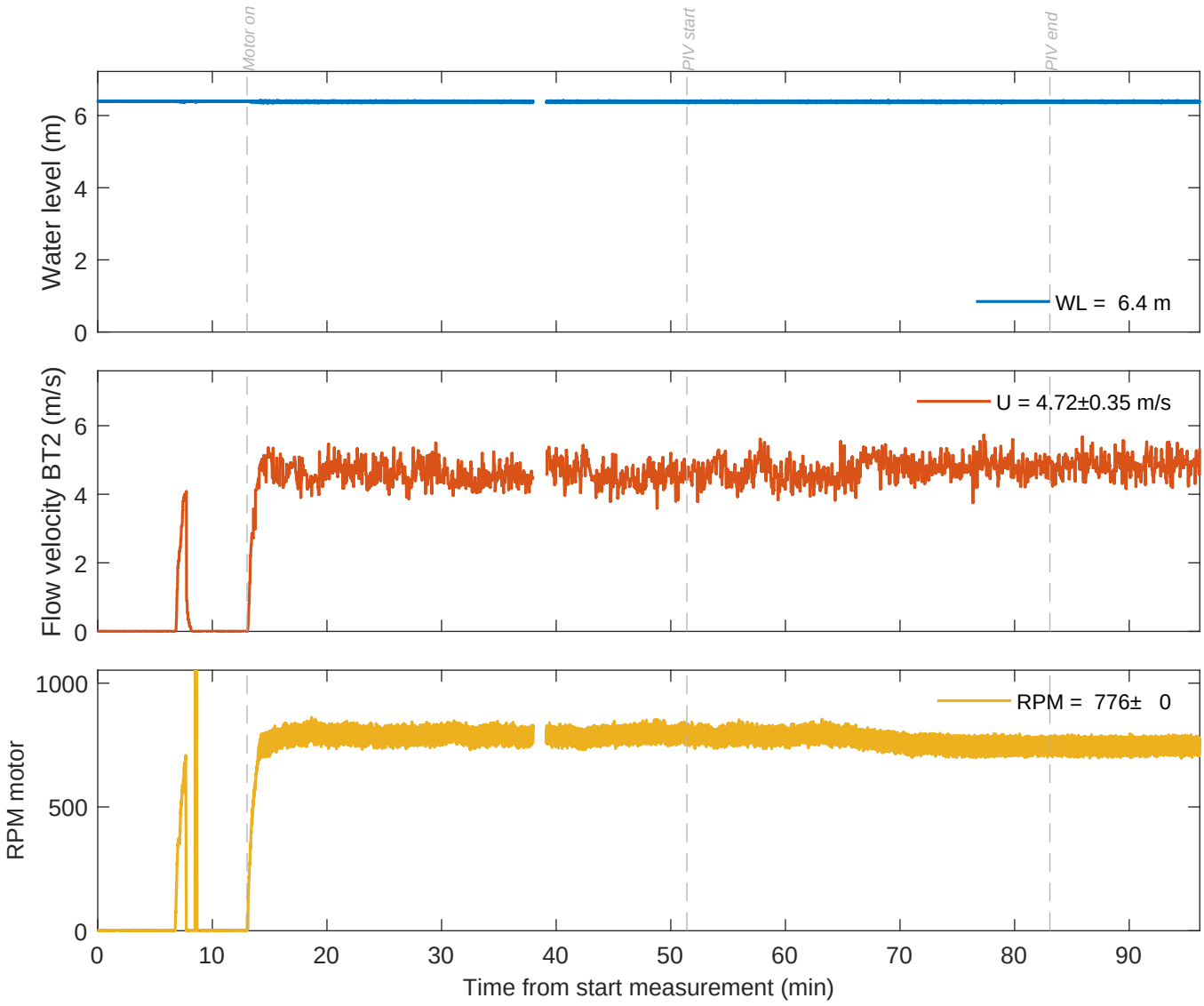
Water level, flow velocity BT2, RPM motor Active thruster: BT2 Δx = 0.8 m, Δy = 0.0 m, UKC = 2.5 m, U_{BT2} = 2.7 m/s	Measurement signals	TKI-SOP
	PIVSOP166	
Deltares	11206641	Fig. C



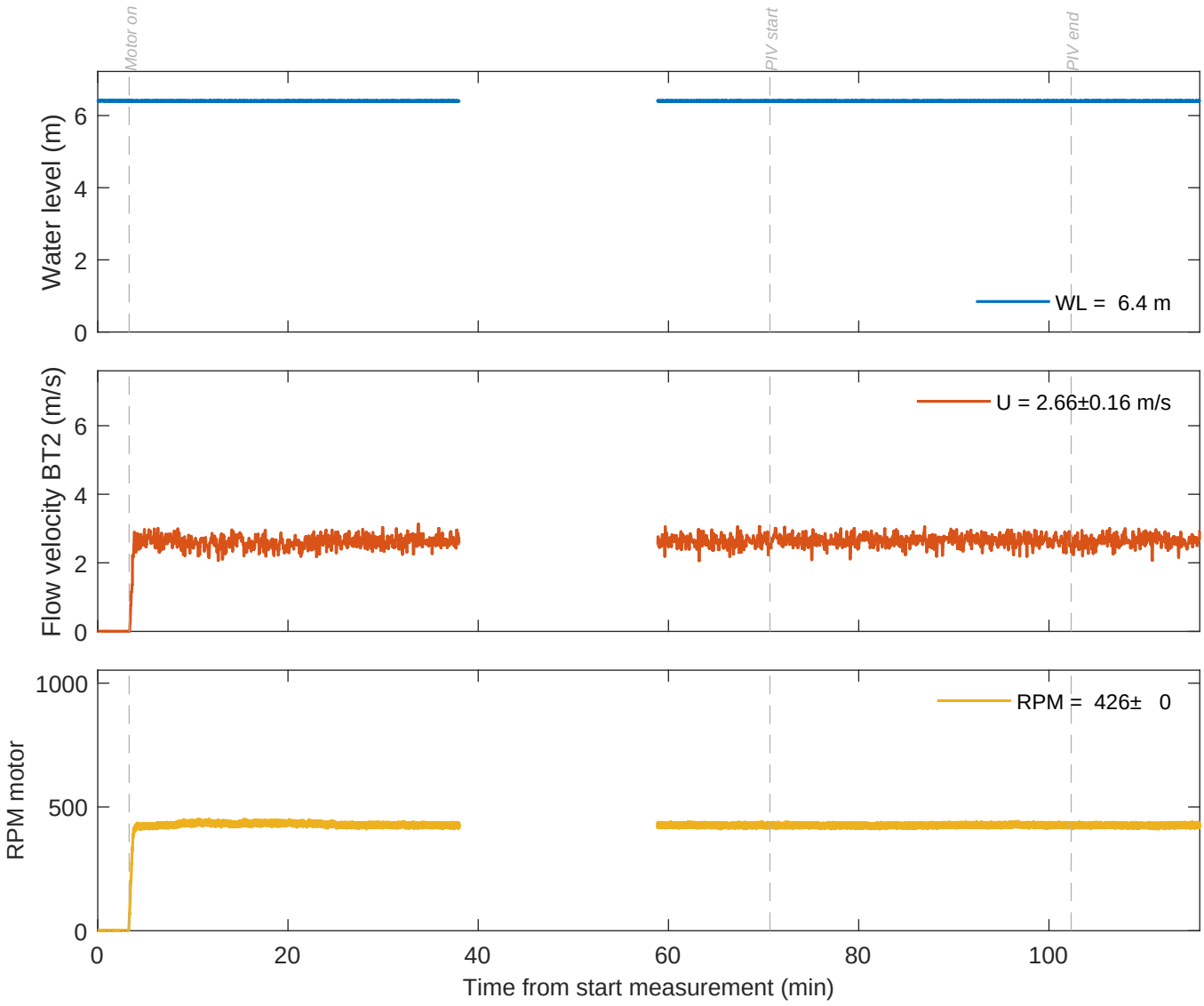
Water level, flow velocity BT2, RPM motor Active thruster: BT2 Δx = 0.8 m, Δy = 0.0 m, UKC = 2.5 m, U_{BT2} = 4.6 m/s	Measurement signals	TKI-SOP
	PIVSOP168	
Deltares	11206641	Fig. C



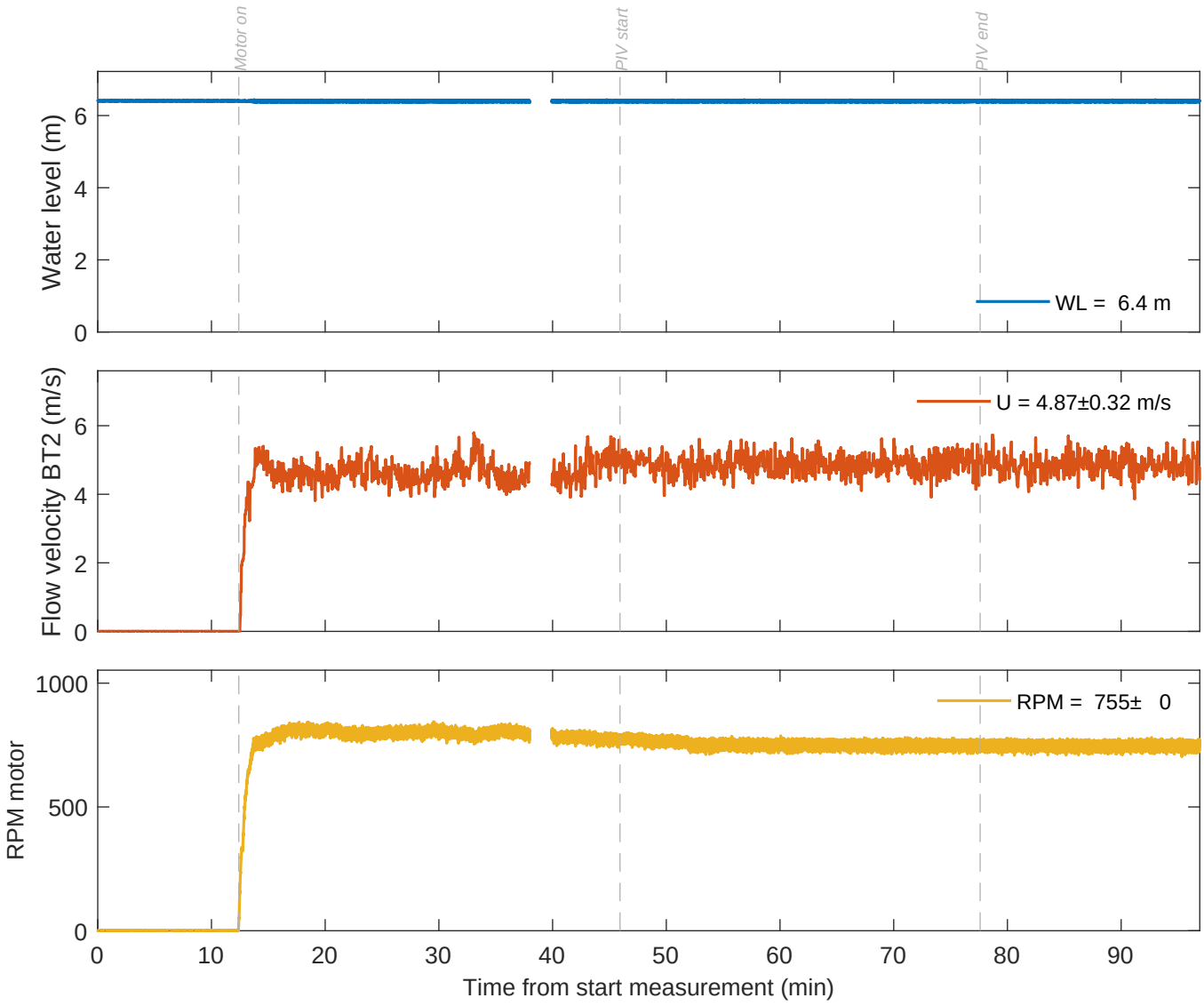
Water level, flow velocity BT2, RPM motor Active thruster: BT2 Δx = 0.8 m, Δy = -2.0 m, UKC = 2.5 m, U_{BT2} = 2.7 m/s	Measurement signals	TKI-SOP
	PIVSOP172	
Deltares	11206641	Fig. C



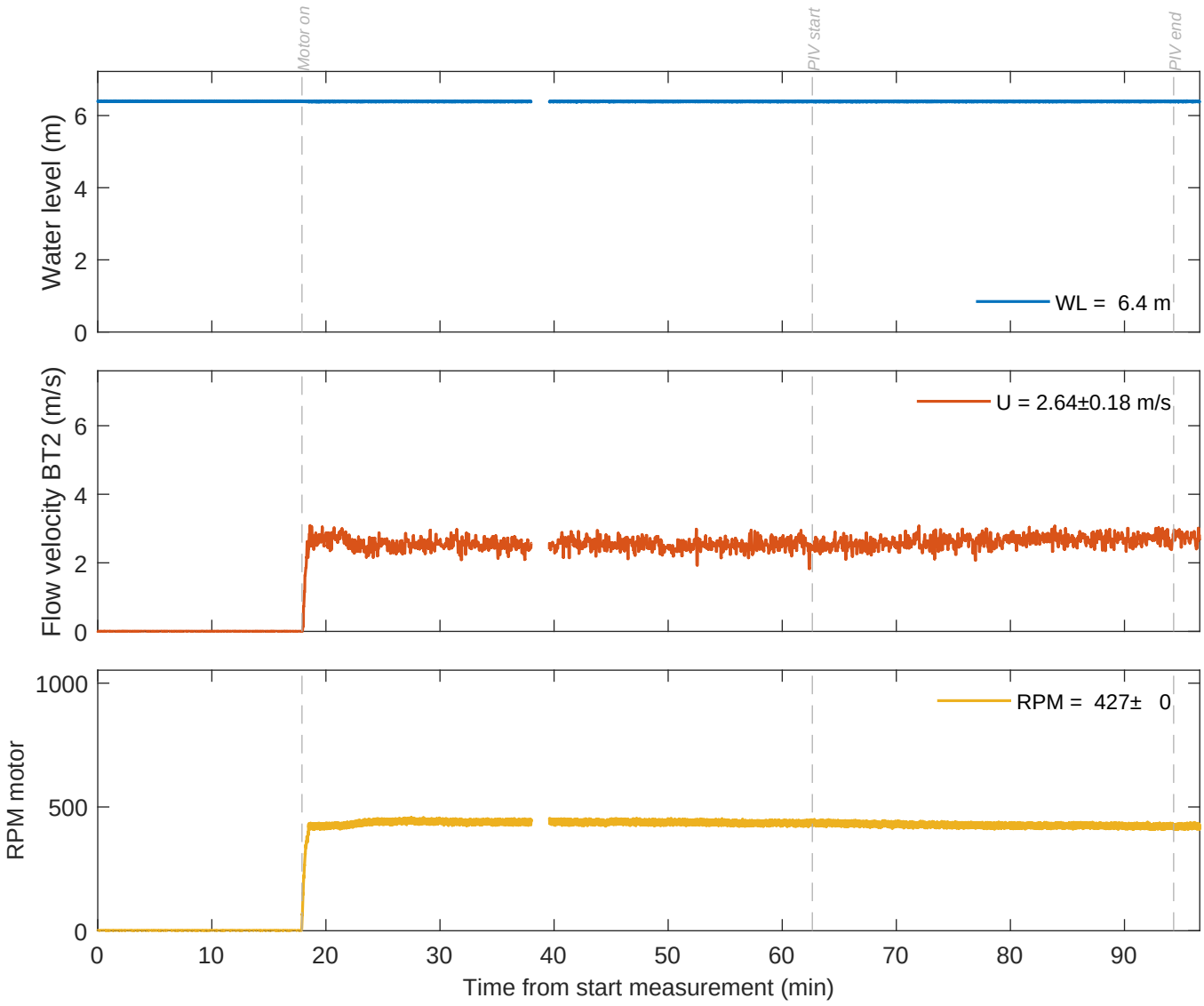
Water level, flow velocity BT2, RPM motor Active thruster: BT2 Δx = 0.8 m, Δy = -2.0 m, UKC = 2.5 m, U_{BT2} = 4.7 m/s	Measurement signals	TKI-SOP
	PIVSOP174	
Deltares	11206641	Fig. C



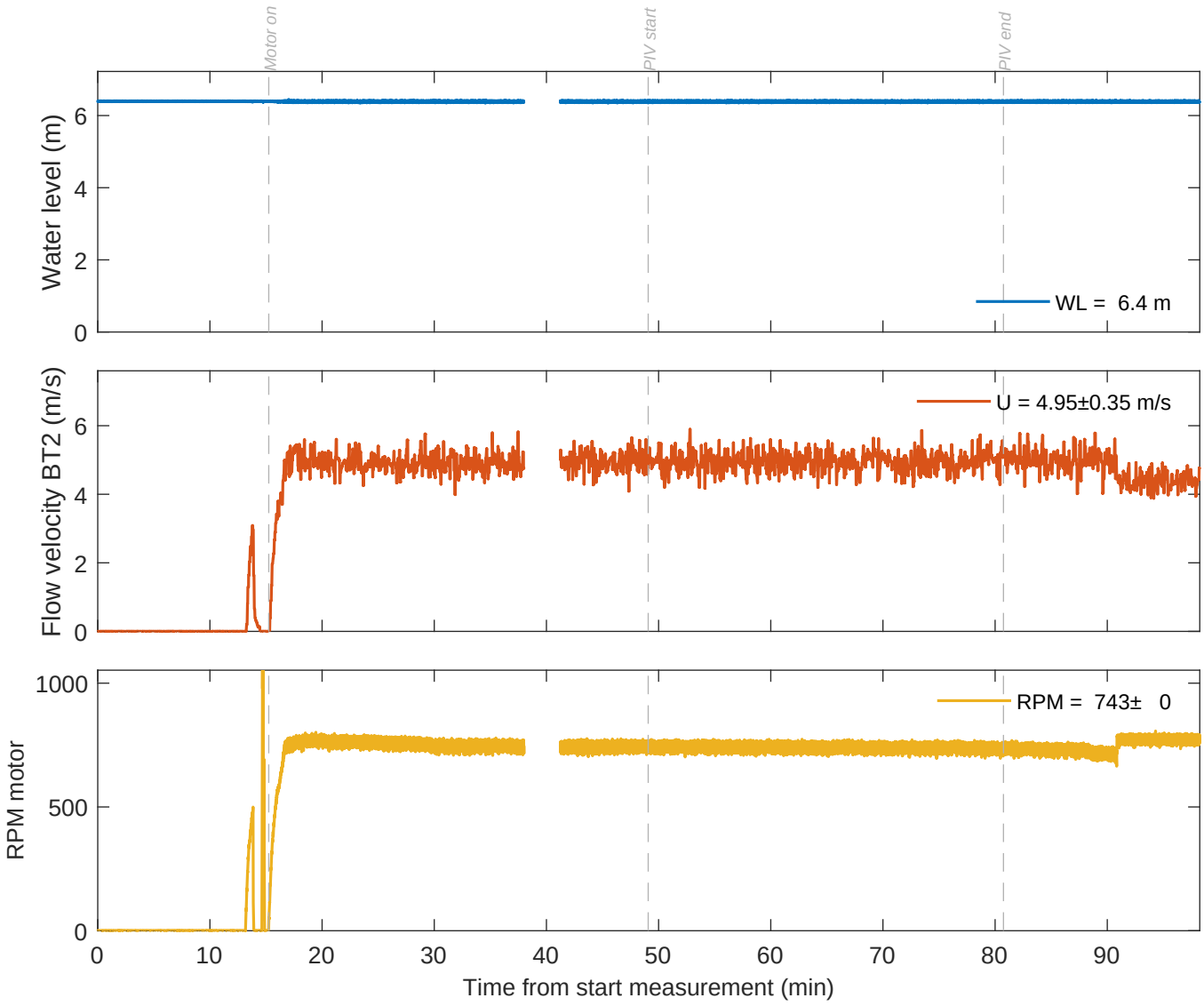
Water level, flow velocity BT2, RPM motor Active thruster: BT2 Δx = 0.8 m, Δy = 0.0 m, UKC = 2.5 m, U_{BT2} = 2.7 m/s	Measurement signals	TKI-SOP
	PIVSOP178	
Deltares	11206641	Fig. C



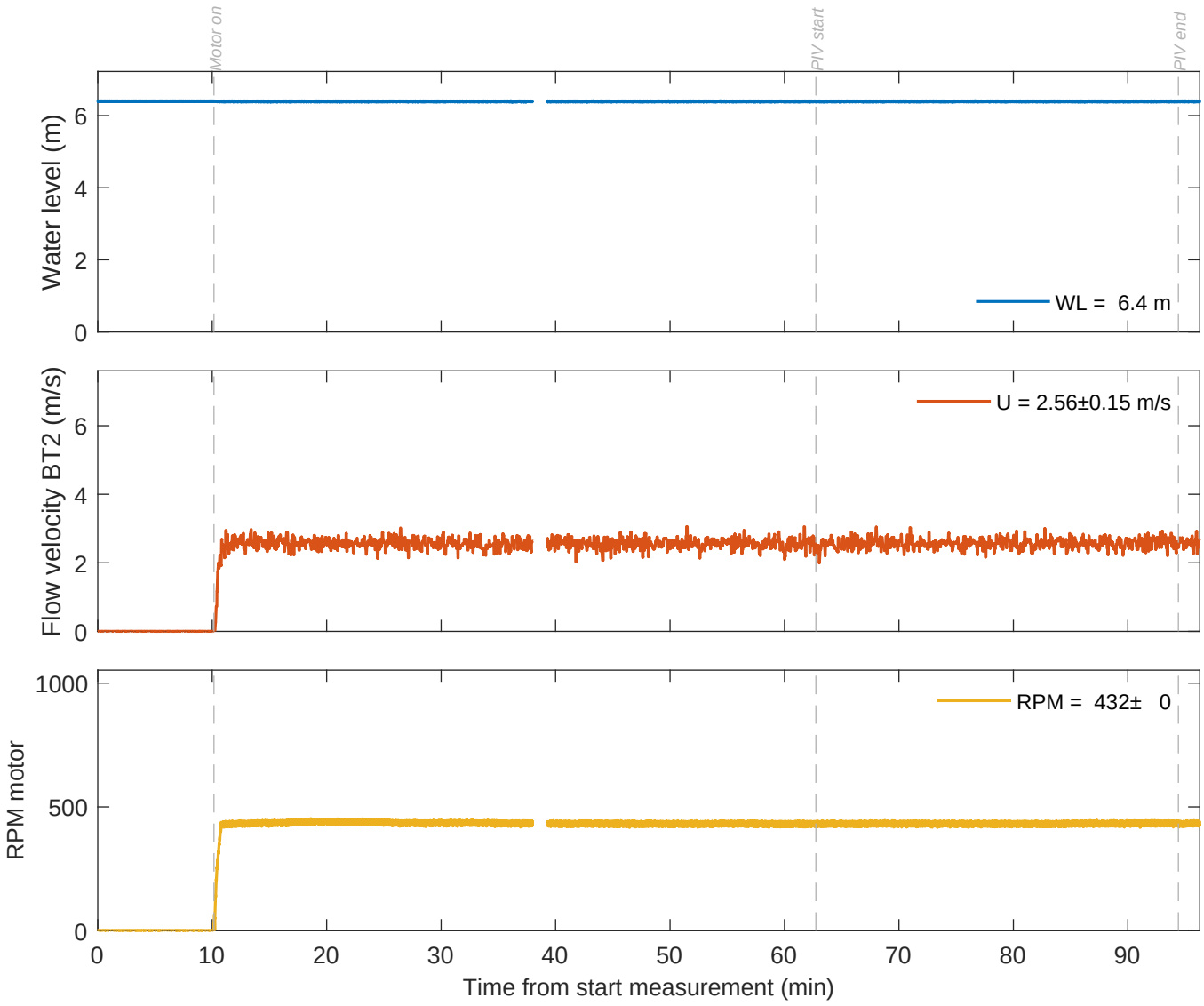
Water level, flow velocity BT2, RPM motor Active thruster: BT2 Δx = 0.8 m, Δy = 0.0 m, UKC = 2.5 m, U_{BT2} = 4.9 m/s	Measurement signals	TKI-SOP
	PIVSOP180	
Deltares	11206641	Fig. C



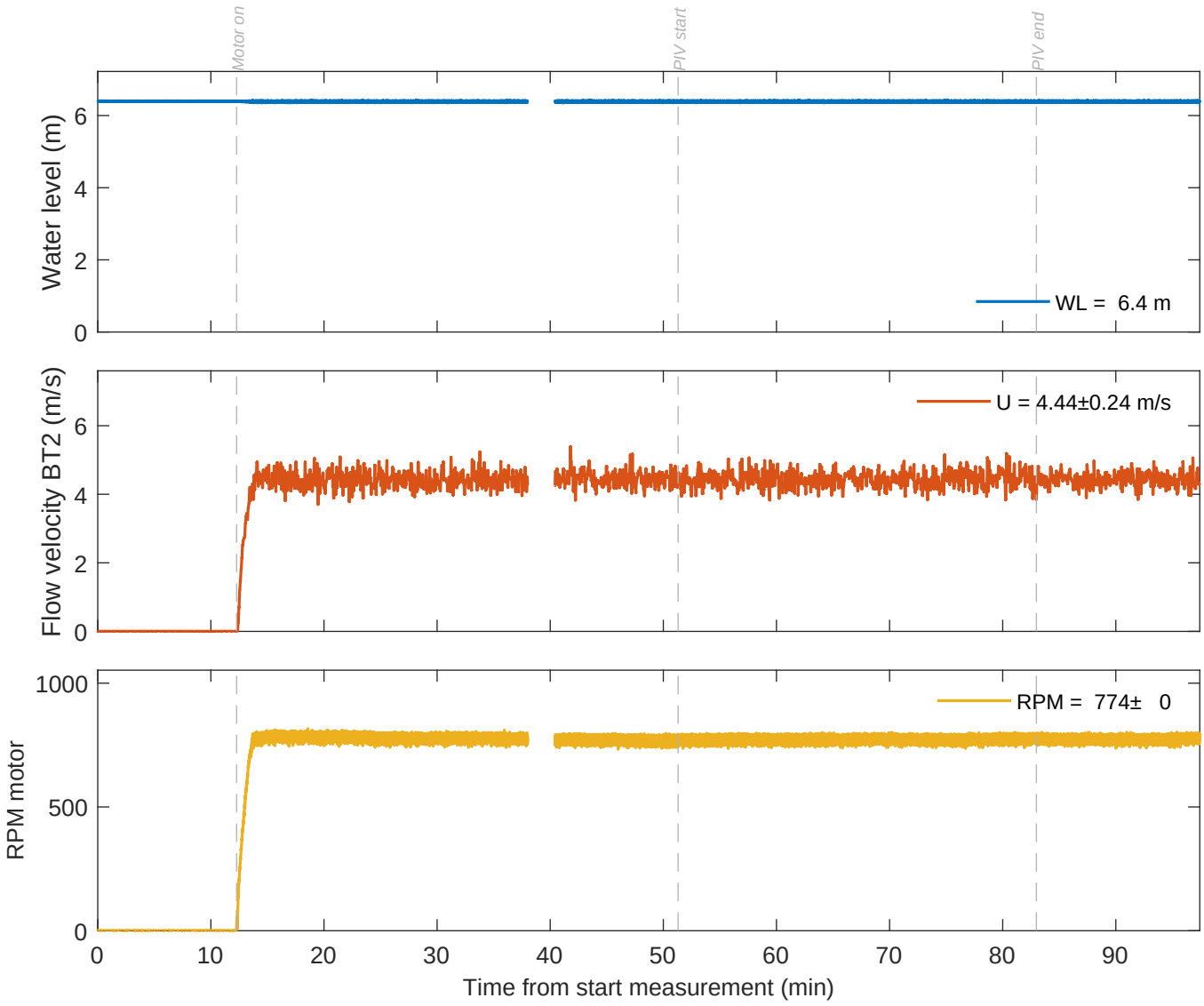
Water level, flow velocity BT2, RPM motor Active thruster: BT2 Δx = 0.8 m, Δy = 0.0 m, UKC = 2.5 m, U_{BT2} = 2.6 m/s	Measurement signals	TKI-SOP
	PIVSOP183	
Deltares	11206641	Fig. C



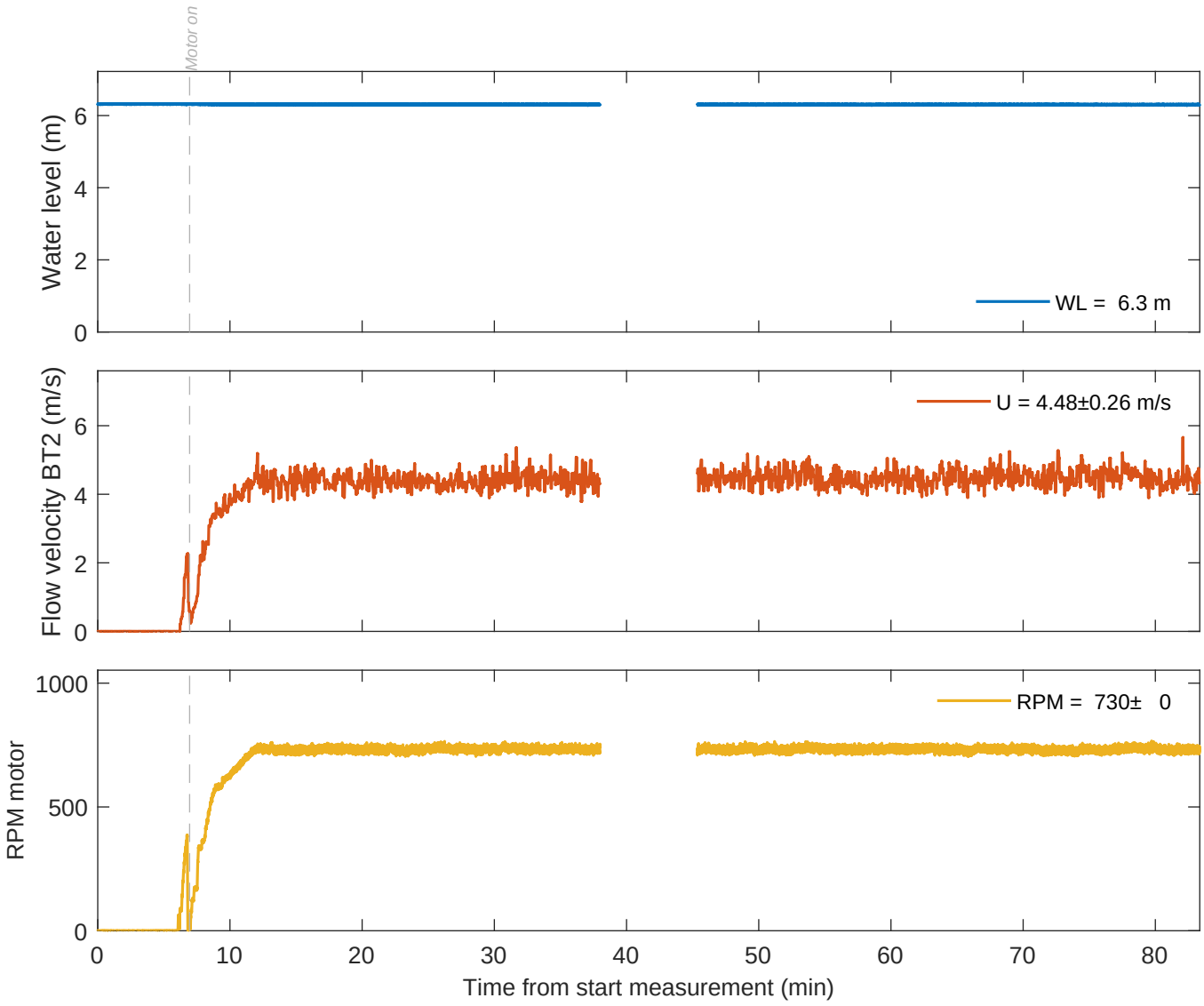
Water level, flow velocity BT2, RPM motor Active thruster: BT2 Δx = 0.8 m, Δy = 0.0 m, UKC = 2.5 m, U_{BT2} = 4.9 m/s	Measurement signals	TKI-SOP
	PIVSOP186	
Deltares	11206641	Fig. C



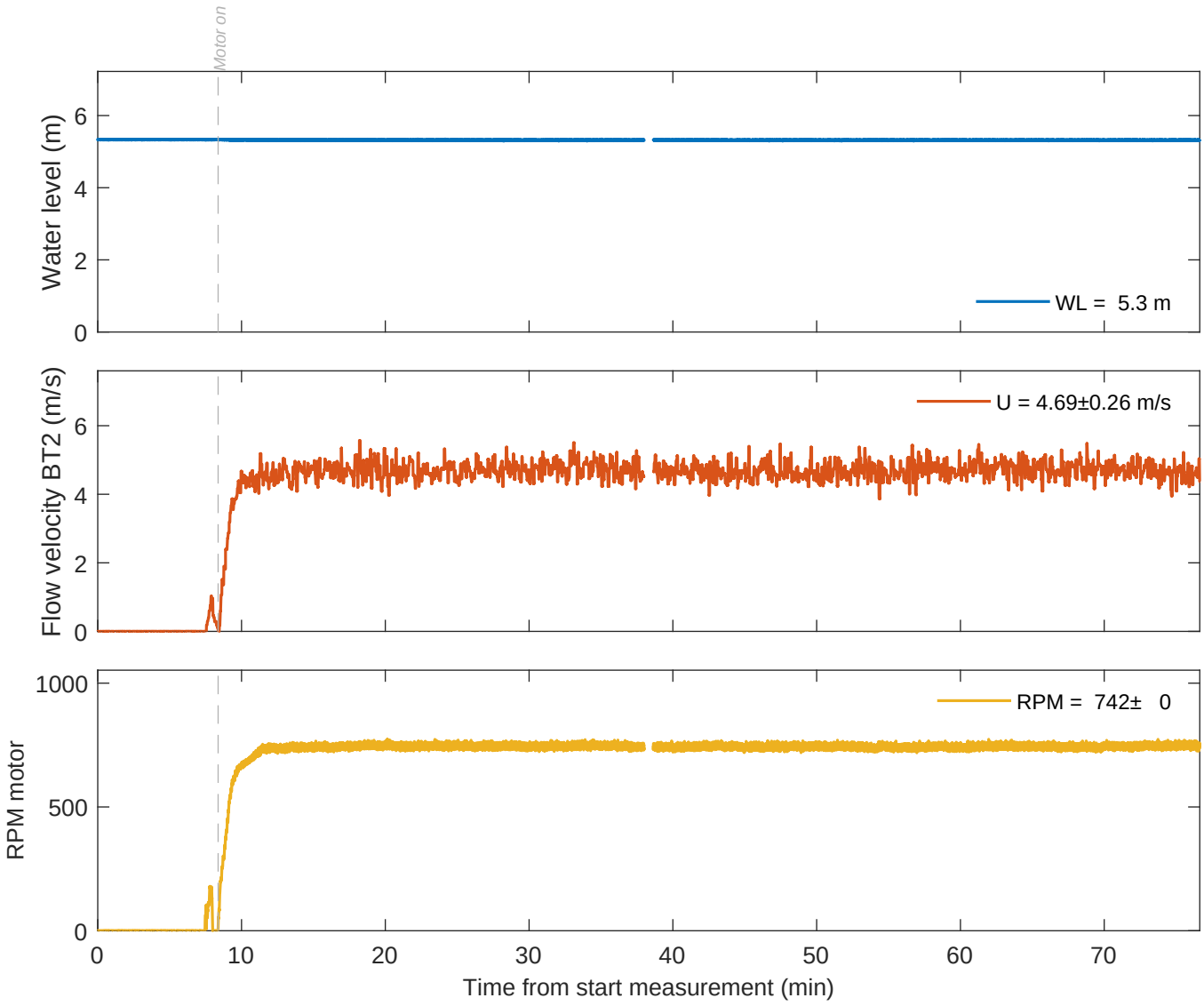
Water level, flow velocity BT2, RPM motor Active thruster: BT2 Δx = 3.0 m, Δy = 0.0 m, UKC = 2.5 m, U_{BT2} = 2.6 m/s	Measurement signals	TKI-SOP
	PIVSOP189	
Deltares	11206641	Fig. C



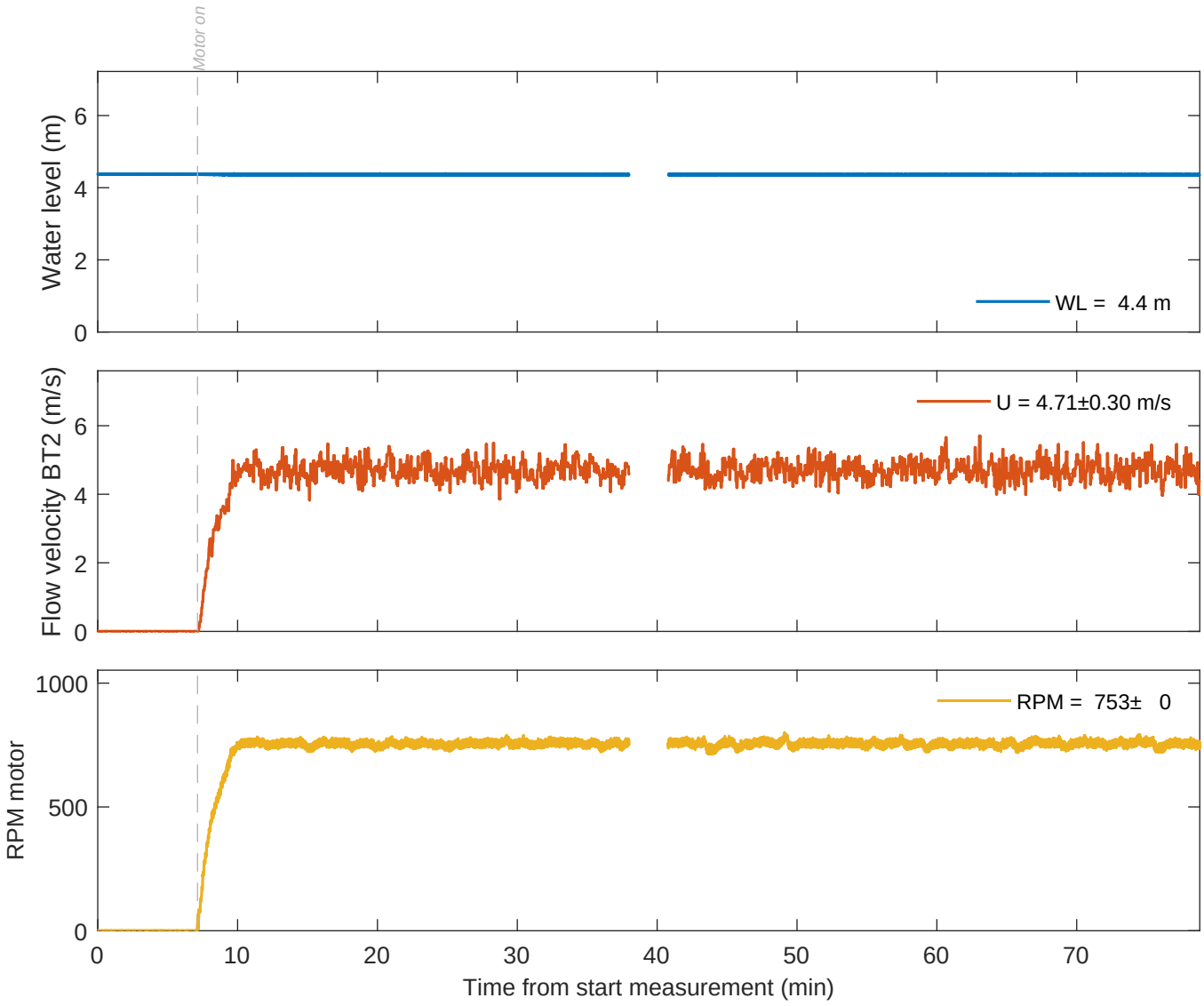
Water level, flow velocity BT2, RPM motor Active thruster: BT2 Δx = 3.0 m, Δy = 0.0 m, UKC = 2.5 m, U_{BT2} = 4.4 m/s	Measurement signals	TKI-SOP
	PIVSOP191	
Deltares	11206641	Fig. C



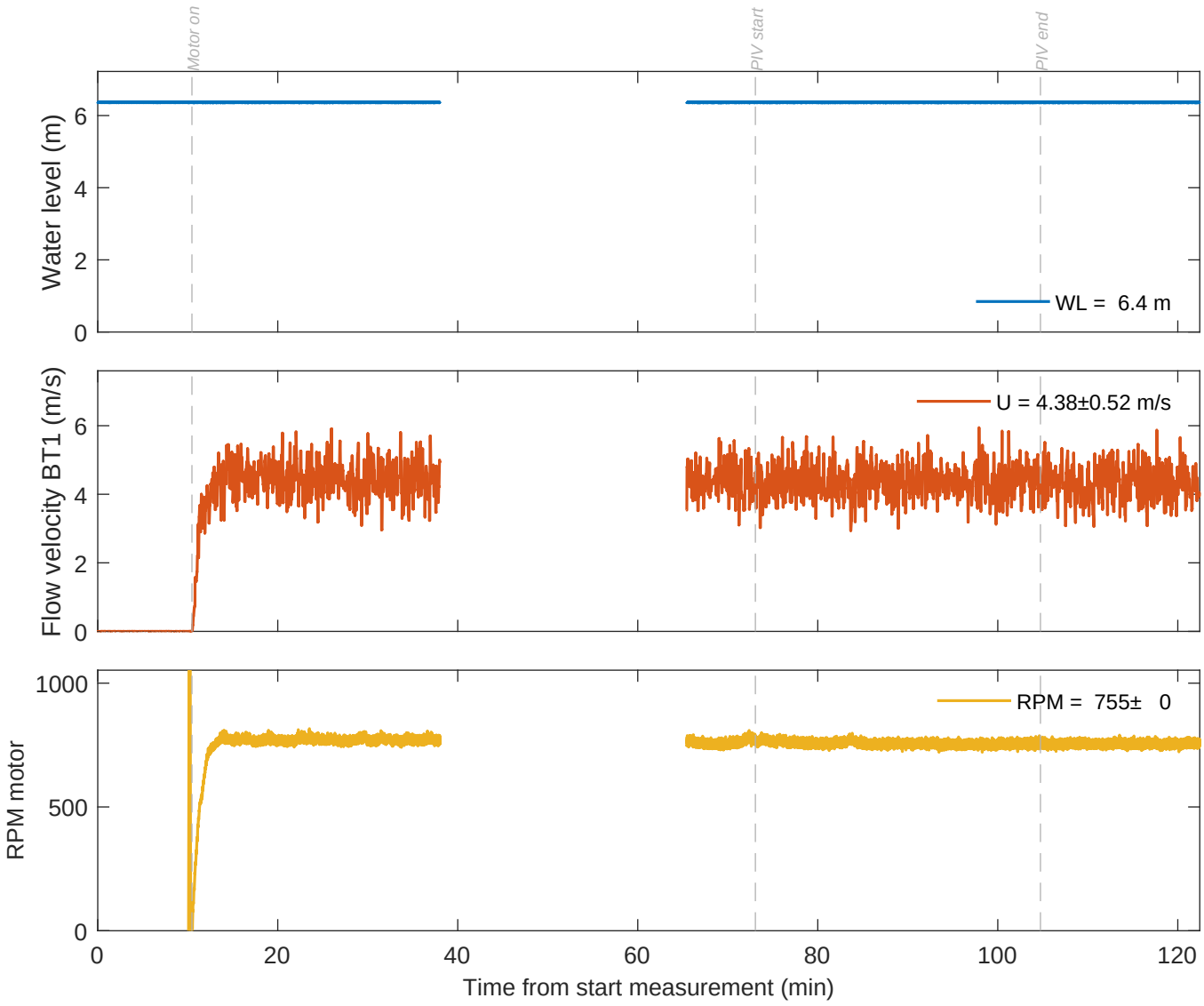
Water level, flow velocity BT2, RPM motor Active thruster: BT2 Δx = 0.8 m, Δy = 0.0 m, UKC = 2.5 m, U_{BT2} = 4.5 m/s	Measurement signals	TKI-SOP
	PIVSOP201	
Deltares	11206641	Fig. C



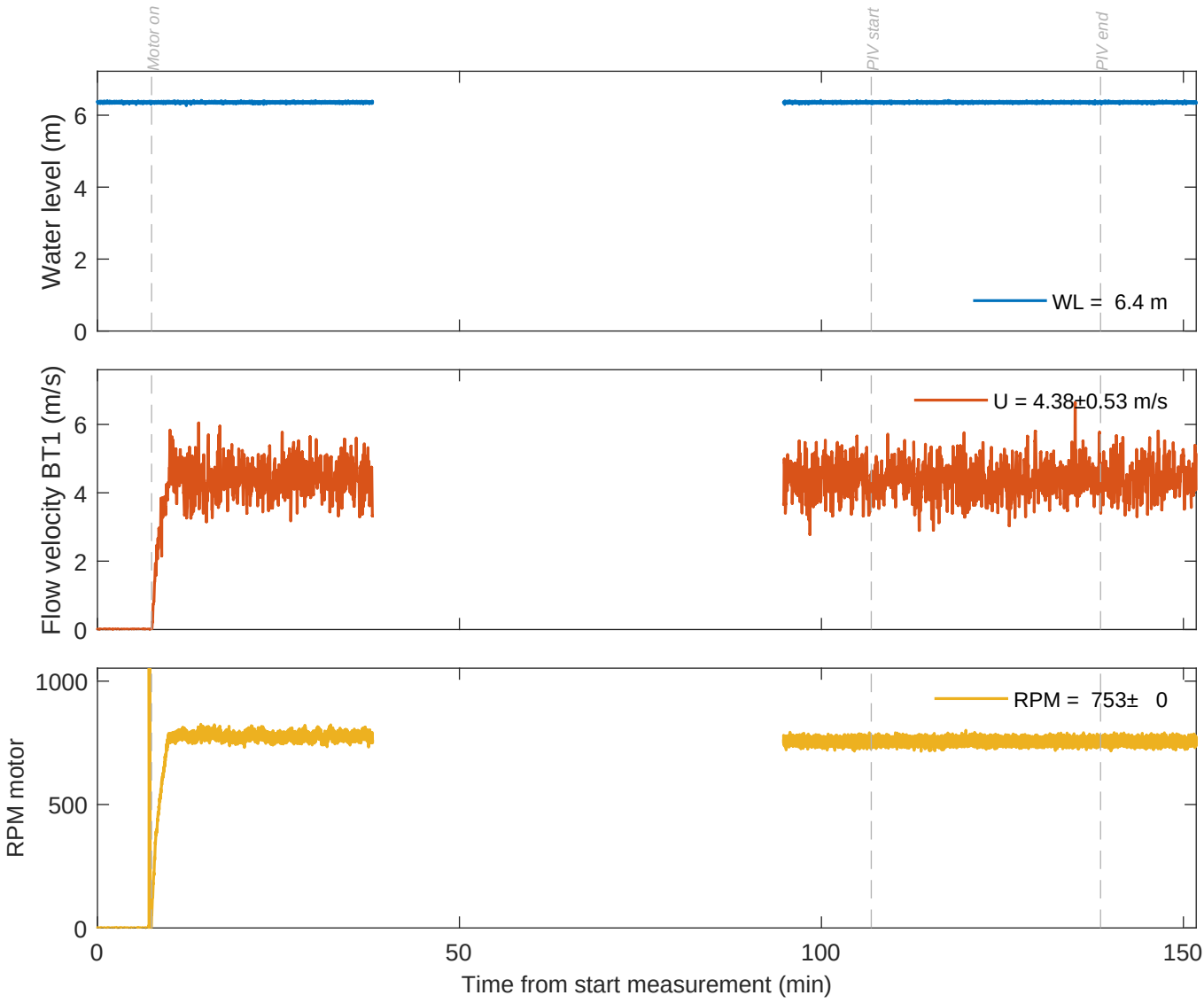
Water level, flow velocity BT2, RPM motor Active thruster: BT2 Δx = 0.8 m, Δy = 0.0 m, UKC = 1.5 m, U_{BT2} = 4.7 m/s	Measurement signals	TKI-SOP
	PIVSOP206	
Deltares	11206641	Fig. C



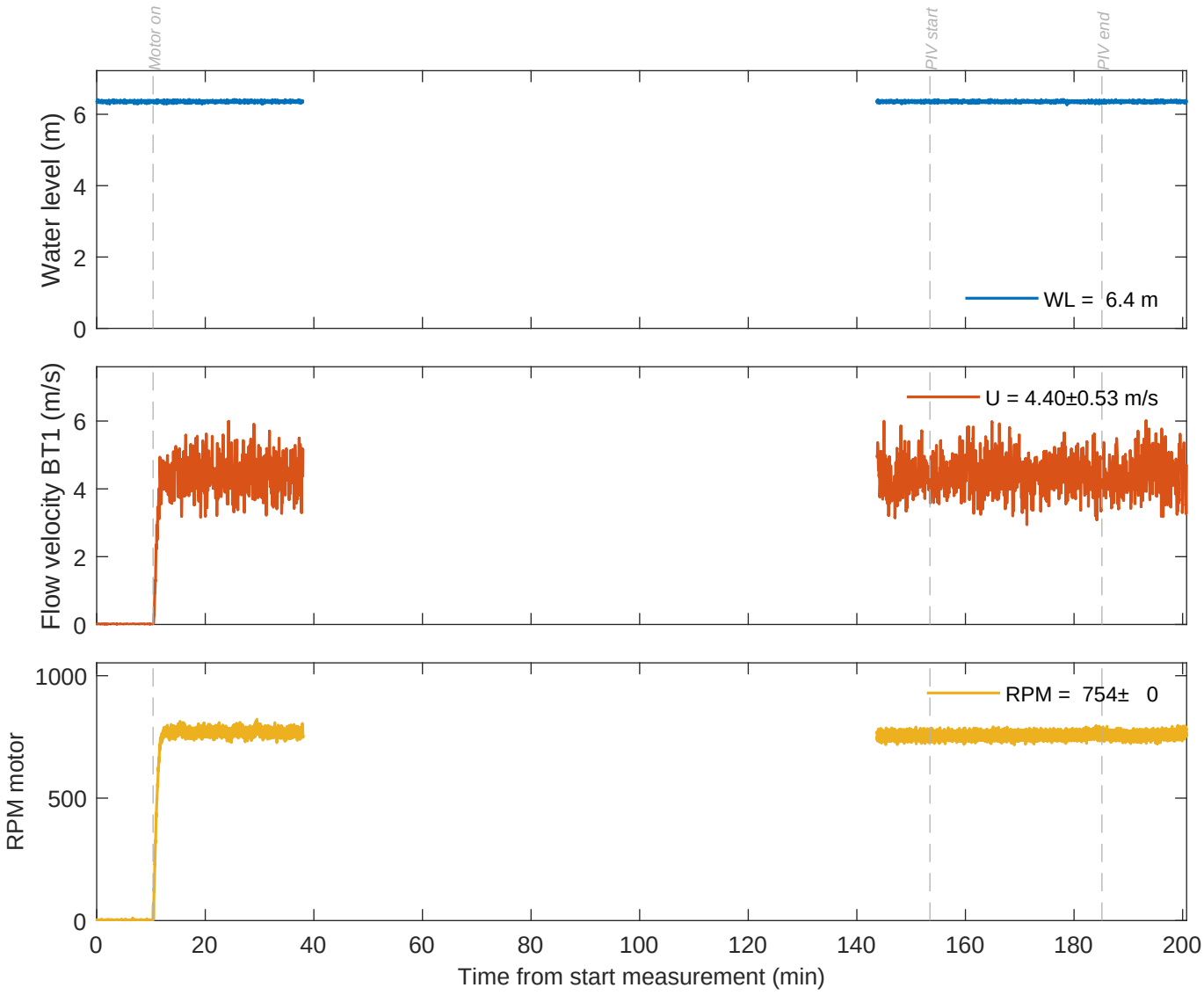
Water level, flow velocity BT2, RPM motor Active thruster: BT2 Δx = 0.8 m, Δy = 0.0 m, UKC = 0.5 m, U_{BT2} = 4.7 m/s	Measurement signals	TKI-SOP
	PIVSOP209	
Deltares	11206641	Fig. C



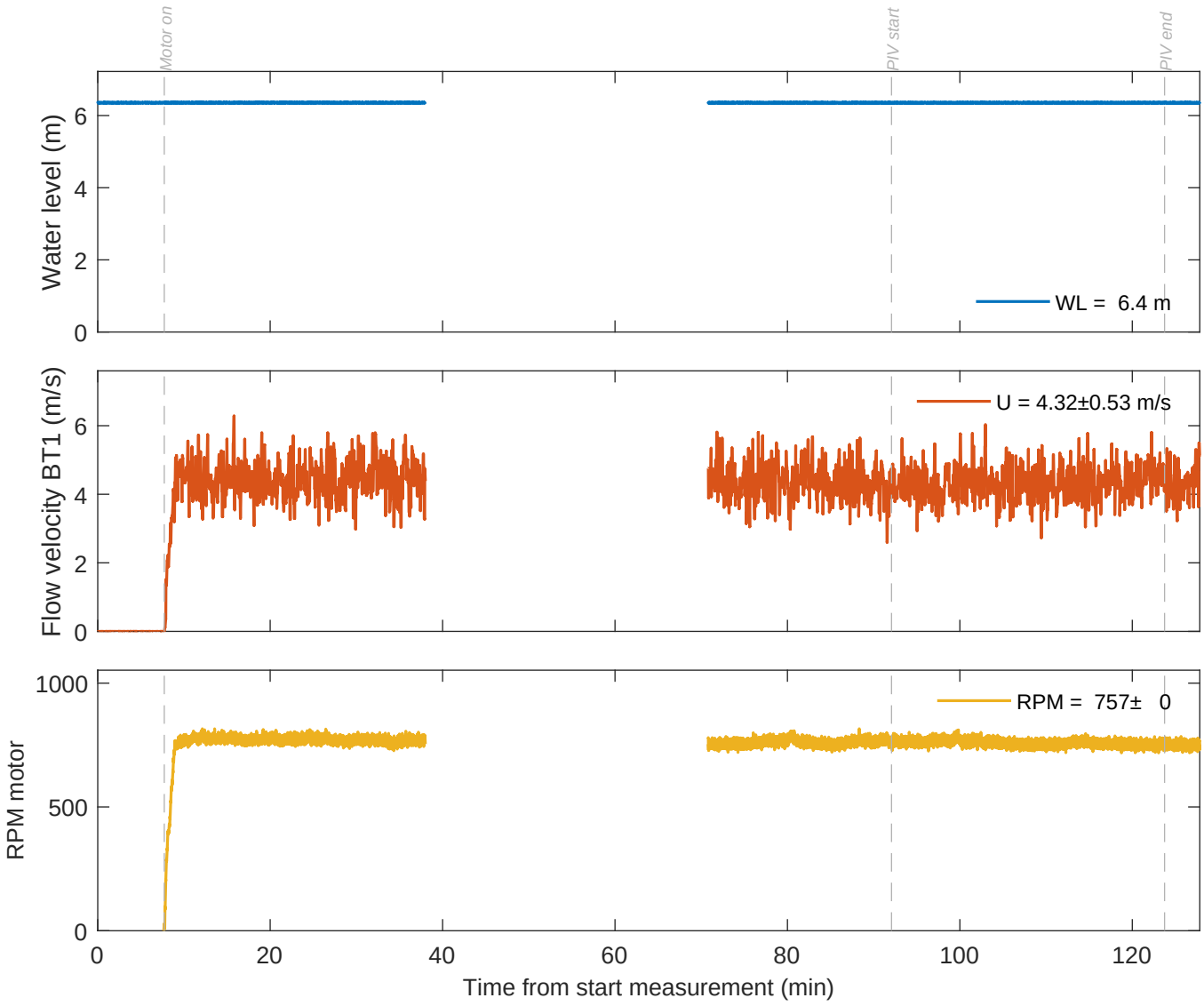
Water level, flow velocity BT1, RPM motor Active thruster: BT1 Δx = 0.8 m, Δy = 2.0 m, UKC = 2.5 m, U_{BT1} = 4.4 m/s	Measurement signals	TKI-SOP
	PIVSOP218	
Deltares	11206641	Fig. C



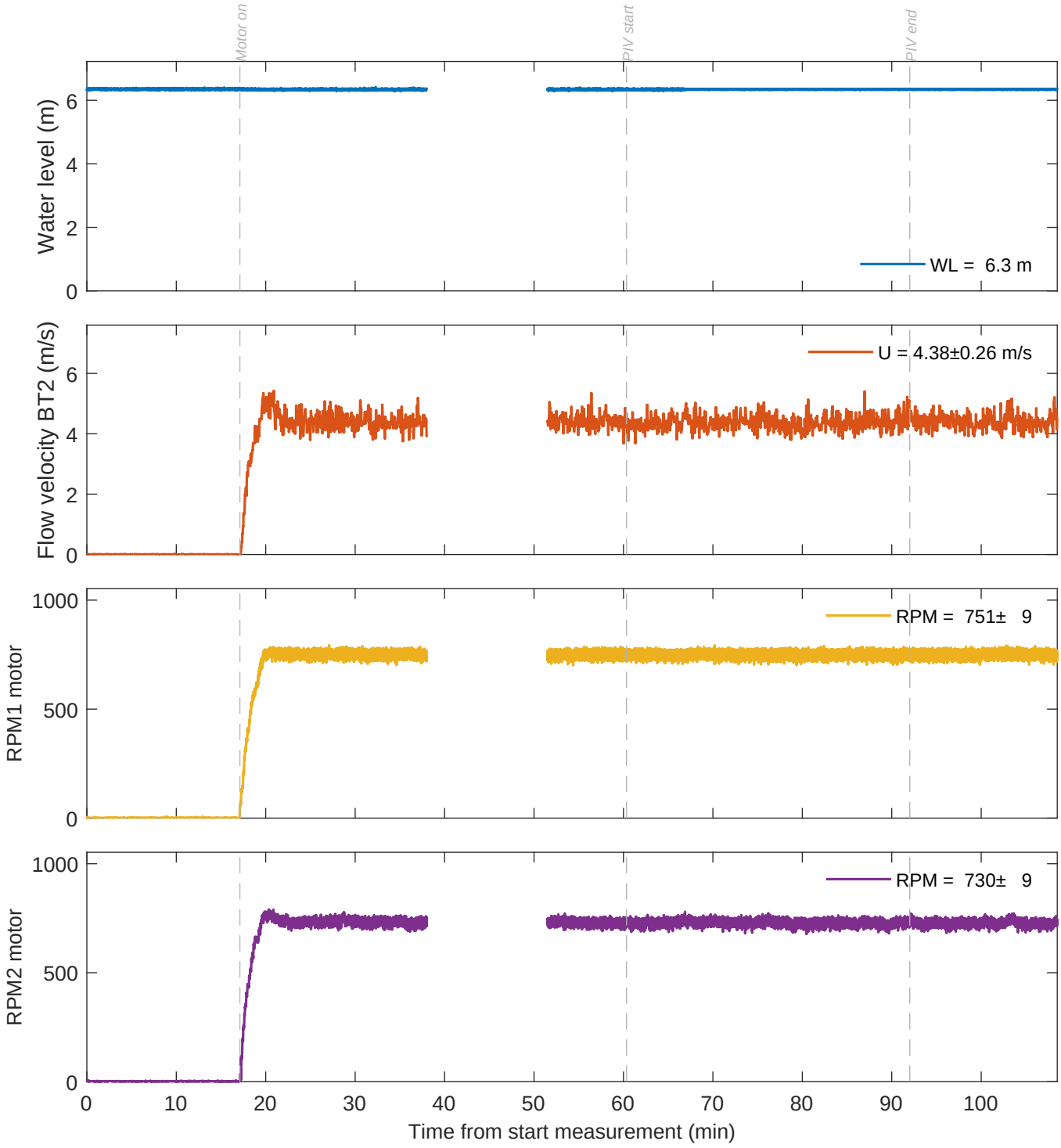
Water level, flow velocity BT1, RPM motor Active thruster: BT1 Δx = 0.8 m, Δy = 3.5 m, UKC = 2.5 m, U_{BT1} = 4.4 m/s	Measurement signals	TKI-SOP
	PIVSOP221	
Deltares	11206641	Fig. C



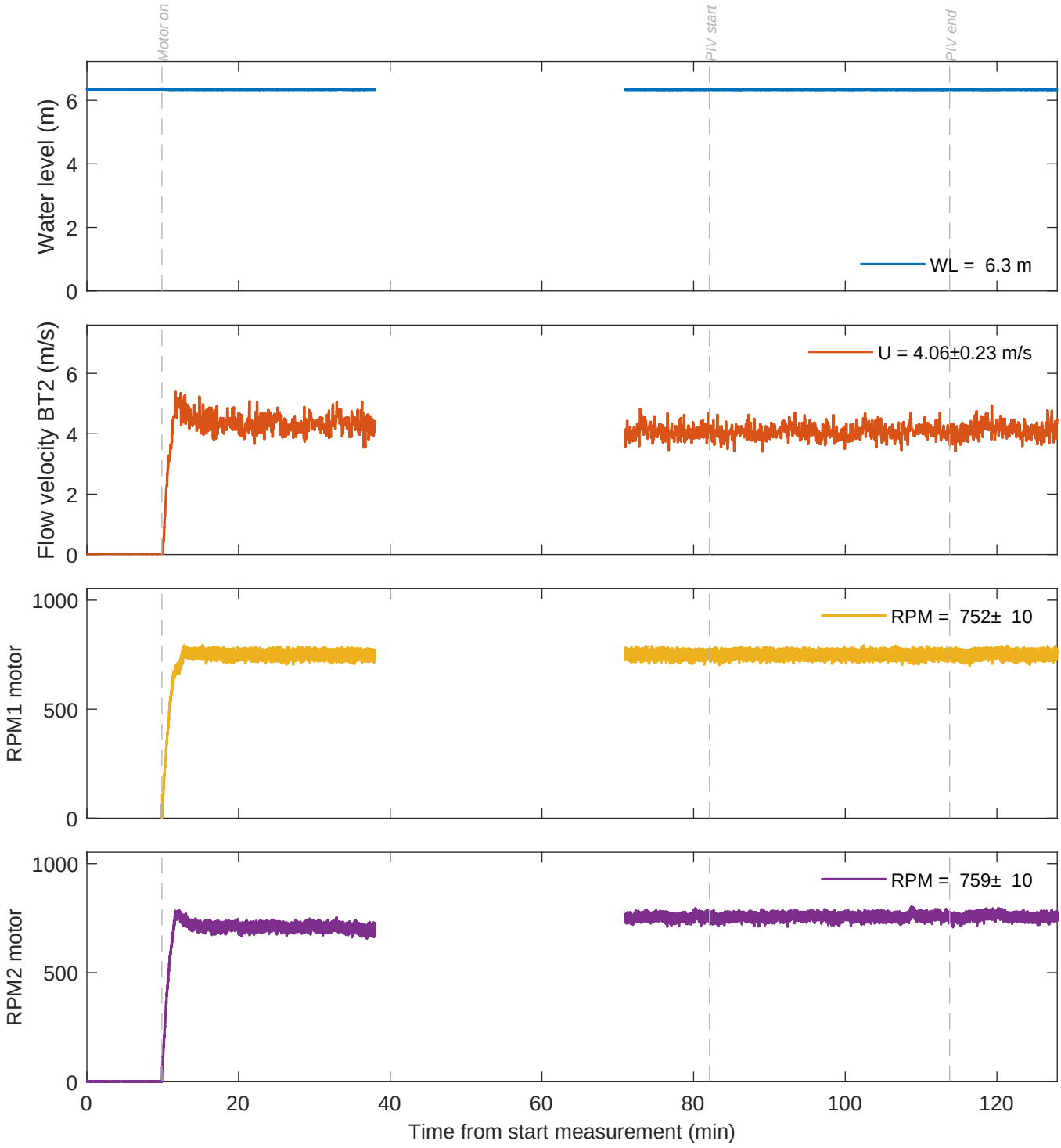
Water level, flow velocity BT1, RPM motor Active thruster: BT1 Δx = 0.8 m, Δy = 0.0 m, UKC = 2.5 m, U_{BT1} = 4.4 m/s	Measurement signals	TKI-SOP
	PIVSOP223	
Deltares	11206641	Fig. C



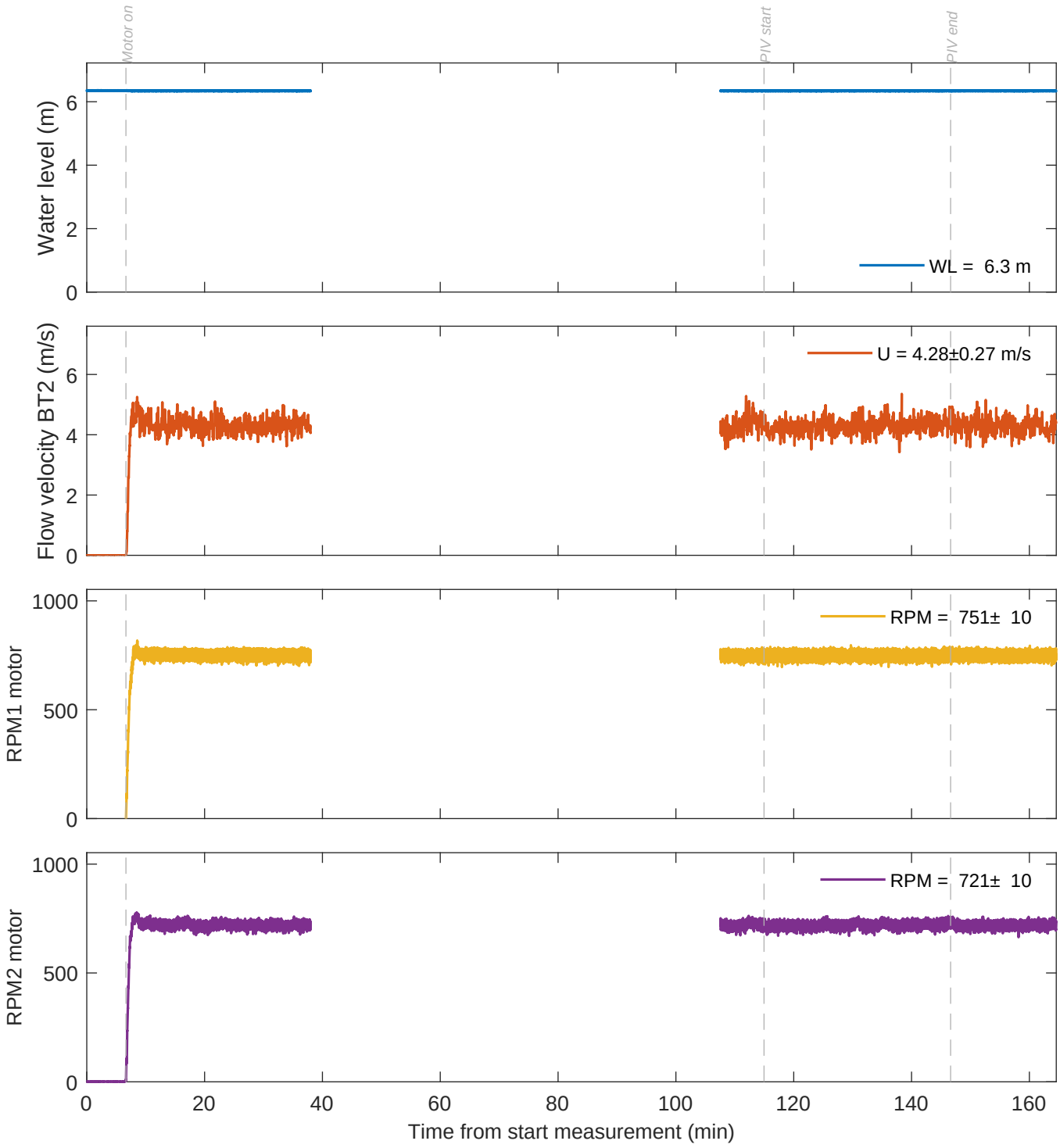
Water level, flow velocity BT1, RPM motor Active thruster: BT1 Δx = 0.8 m, Δy = -2.0 m, UKC = 2.5 m, U_{BT1} = 4.3 m/s	Measurement signals	TKI-SOP
	PIVSOP225	
Deltares	11206641	Fig. C



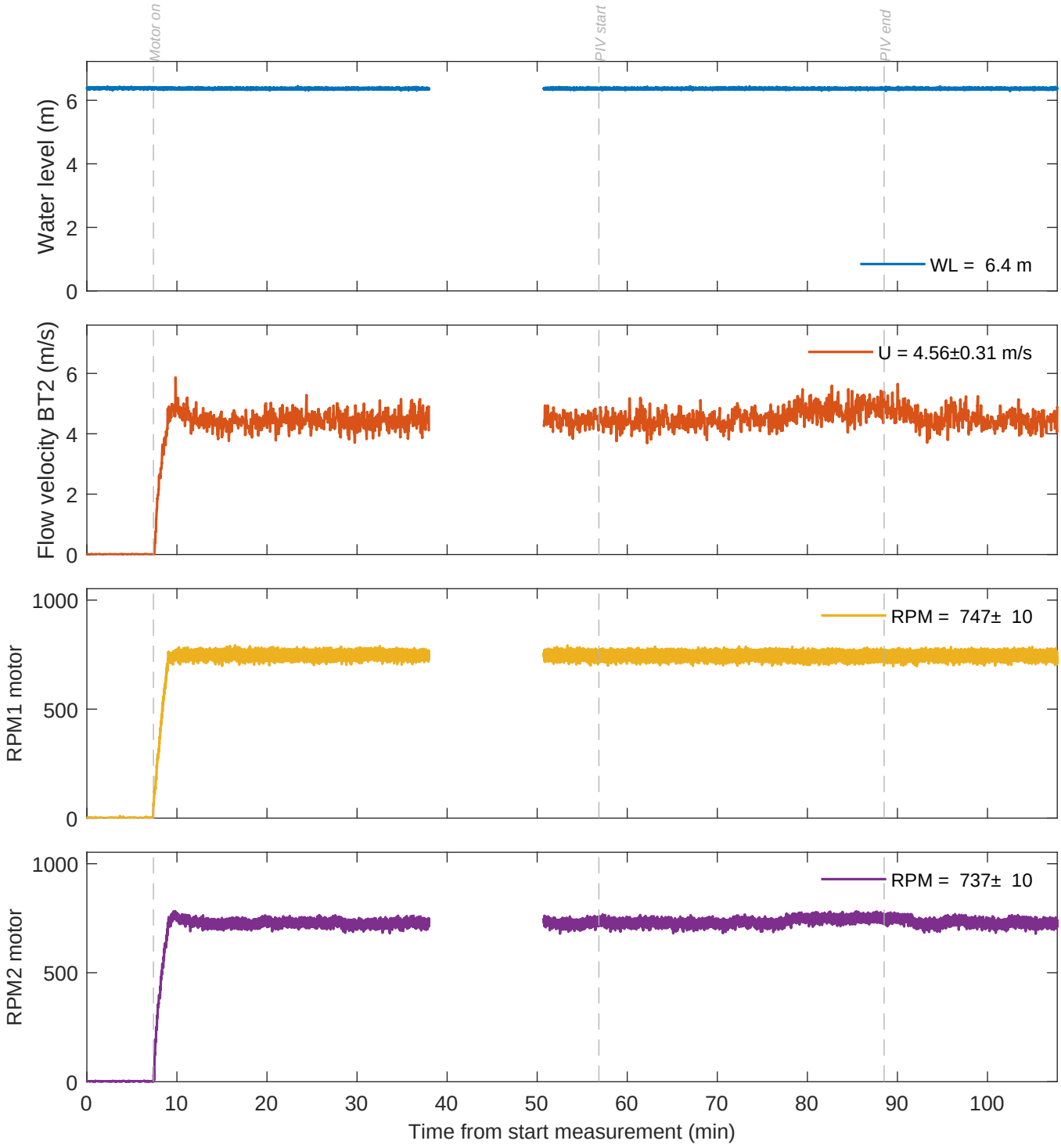
Water level, flow velocity BT2, RPM motor Active thruster: BT1&BT2 Δx = 0.8 m, Δy = 0.0 m, UKC = 2.5 m, U_{BT2} = 4.4 m/s	Measurement signals	TKI-SOP
	PIVSOP231	
Deltares	11206641	Fig. C



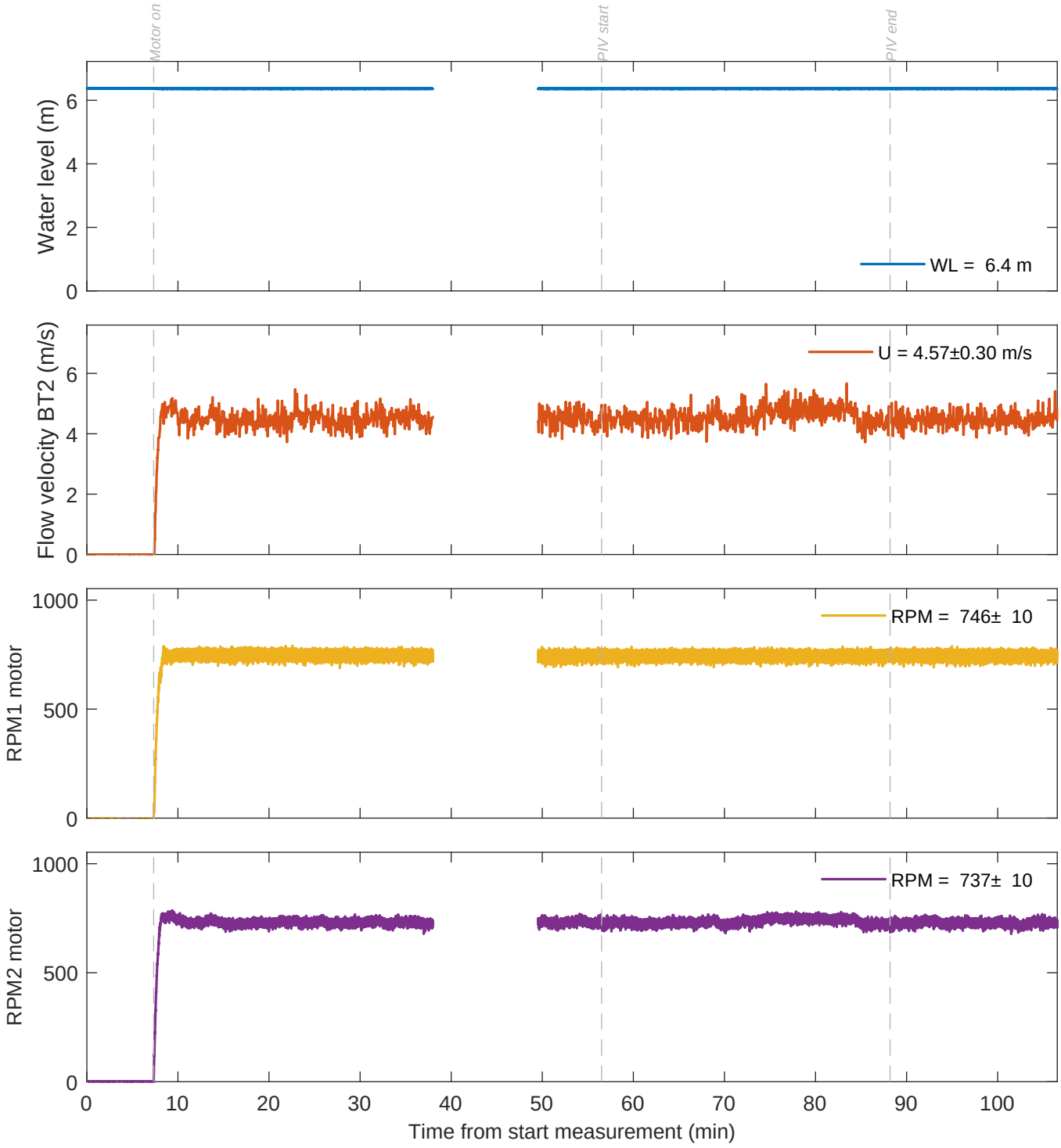
Water level, flow velocity BT2, RPM motor Active thruster: BT1&BT2 Δx = 0.8 m, Δy = 2.0 m, UKC = 2.5 m, U_{BT2} = 4.1 m/s	Measurement signals	TKI-SOP
	PIVSOP233	
Deltares	11206641	Fig. C



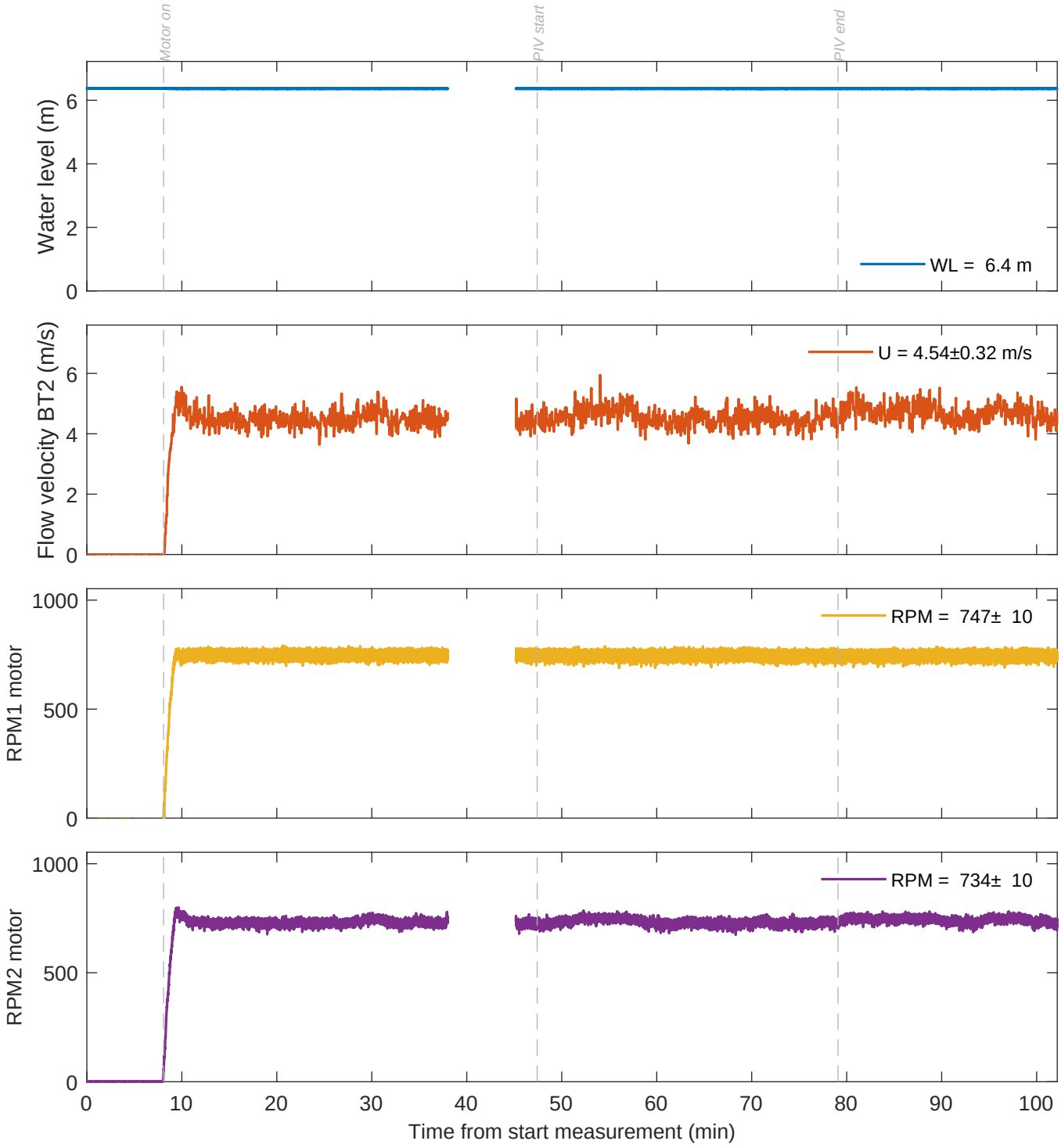
Water level, flow velocity BT2, RPM motor Active thruster: BT1&BT2 Δx = 0.8 m, Δy = 3.5 m, UKC = 2.5 m, U_{BT2} = 4.3 m/s	Measurement signals	TKI-SOP
	PIVSOP235	
Deltares	11206641	Fig. C



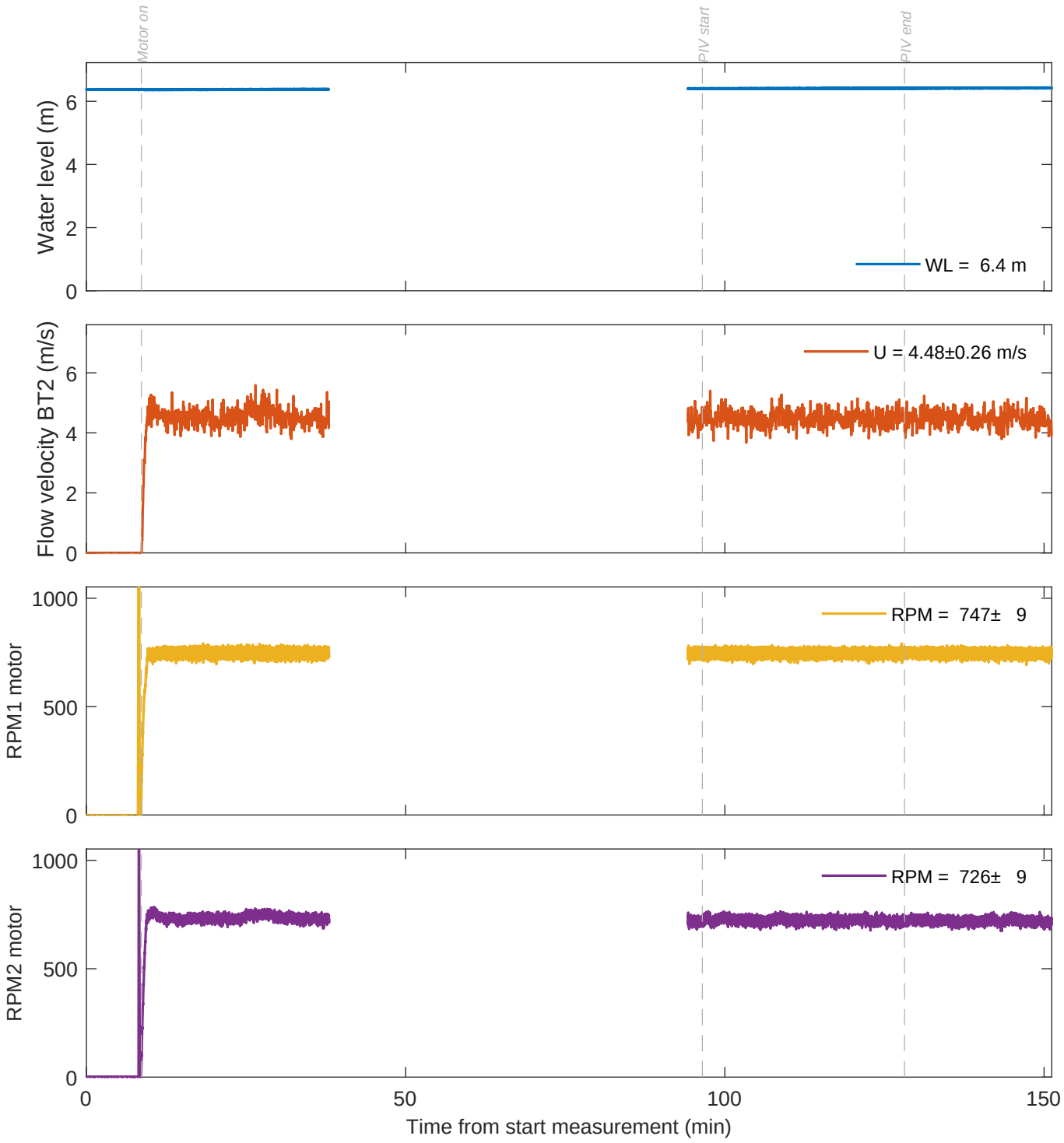
Water level, flow velocity BT2, RPM motor Active thruster: BT1&BT2 Δx = 0.8 m, Δy = 3.5 m, UKC = 2.5 m, U_{BT2} = 4.6 m/s	Measurement signals	TKI-SOP
	PIVSOP238	
Deltares	11206641	Fig. C



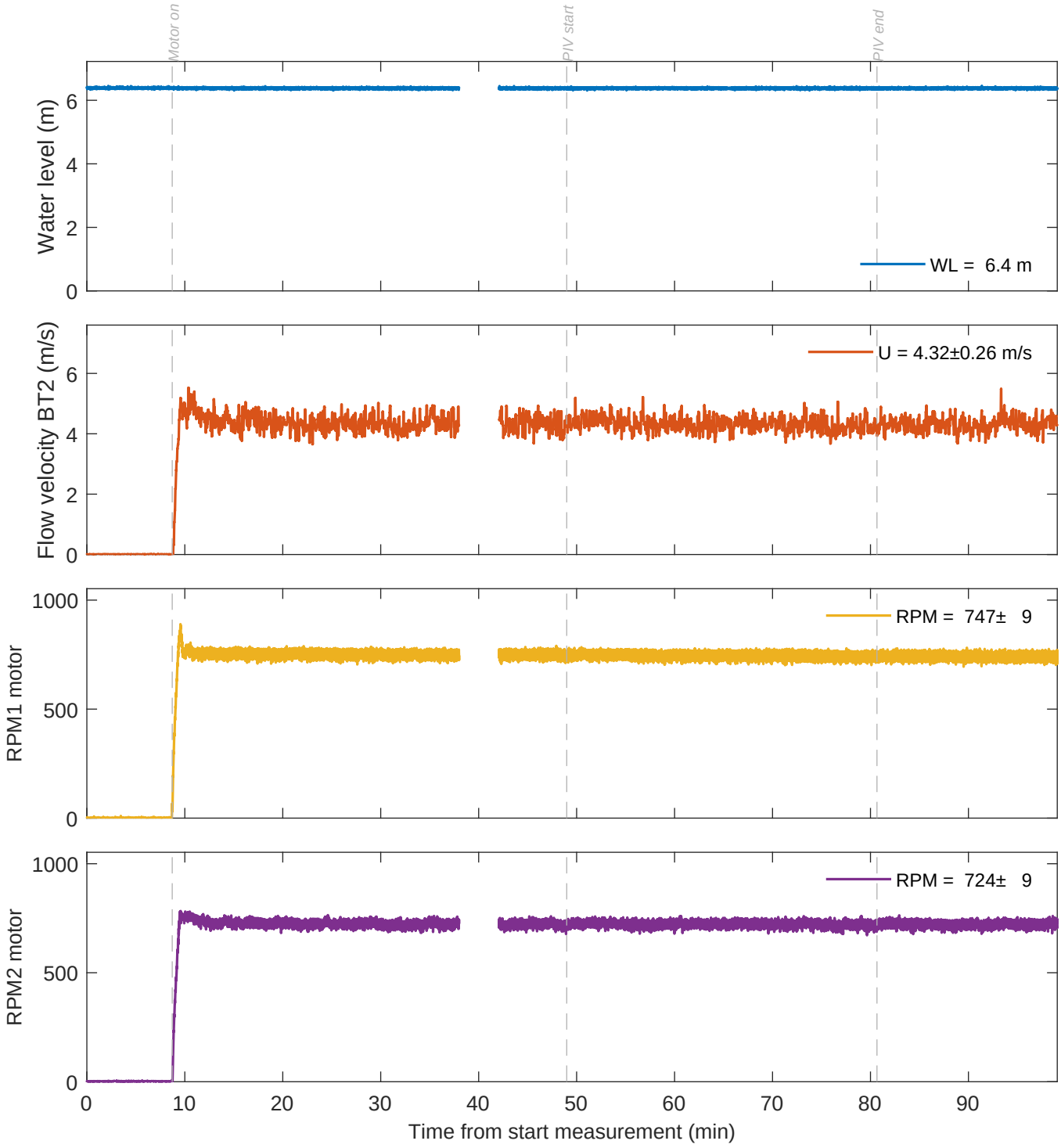
Water level, flow velocity BT2, RPM motor Active thruster: BT1&BT2 Δx = 0.8 m, Δy = 0.0 m, UKC = 2.5 m, U_{BT2} = 4.6 m/s	Measurement signals	TKI-SOP
	PIVSOP242	
Deltares	11206641	Fig. C



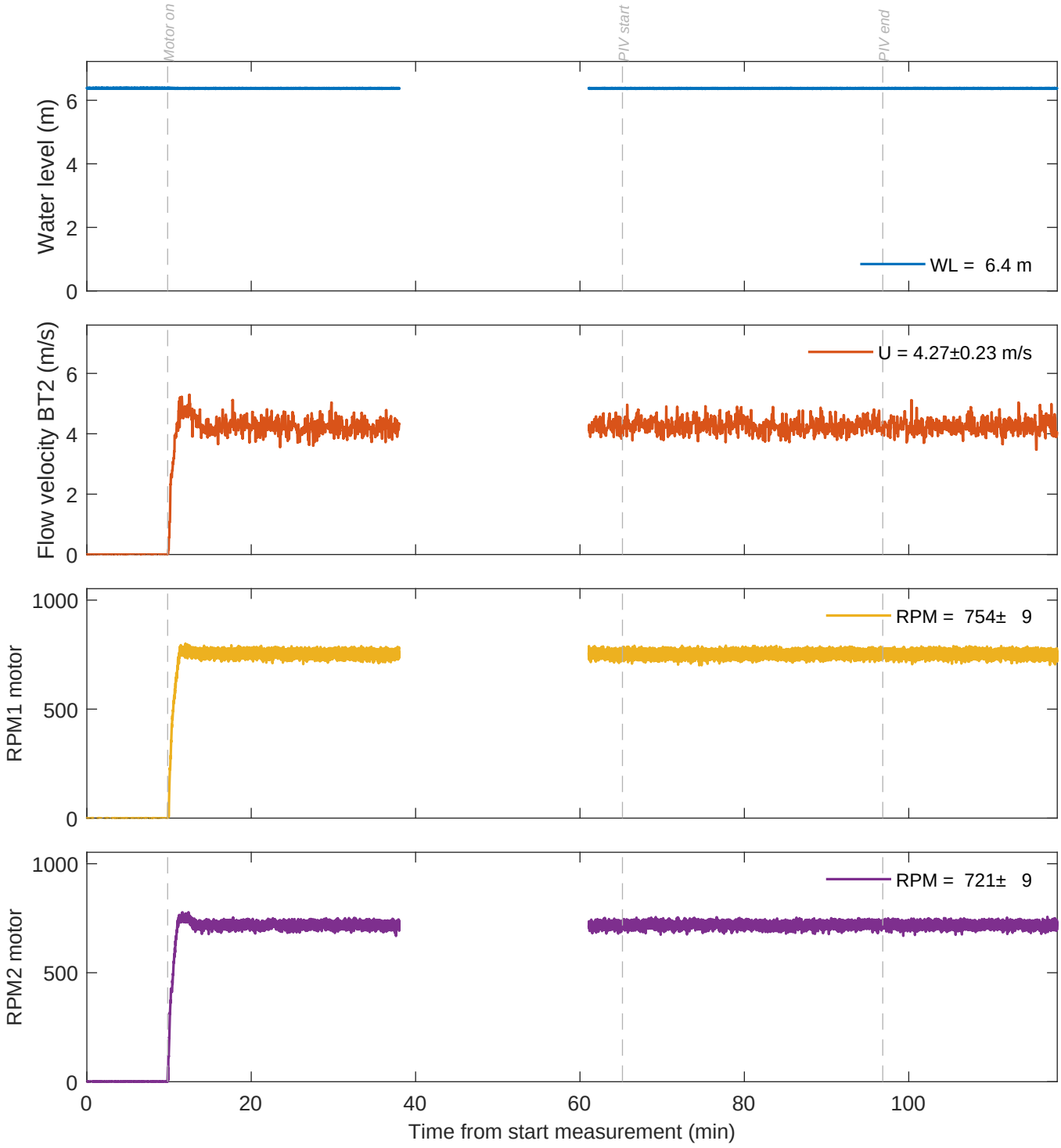
Water level, flow velocity BT2, RPM motor Active thruster: BT1&BT2 Δx = 0.8 m, Δy = 2.0 m, UKC = 2.5 m, U_{BT2} = 4.5 m/s	Measurement signals	TKI-SOP
	PIVSOP244	
Deltares	11206641	Fig. C



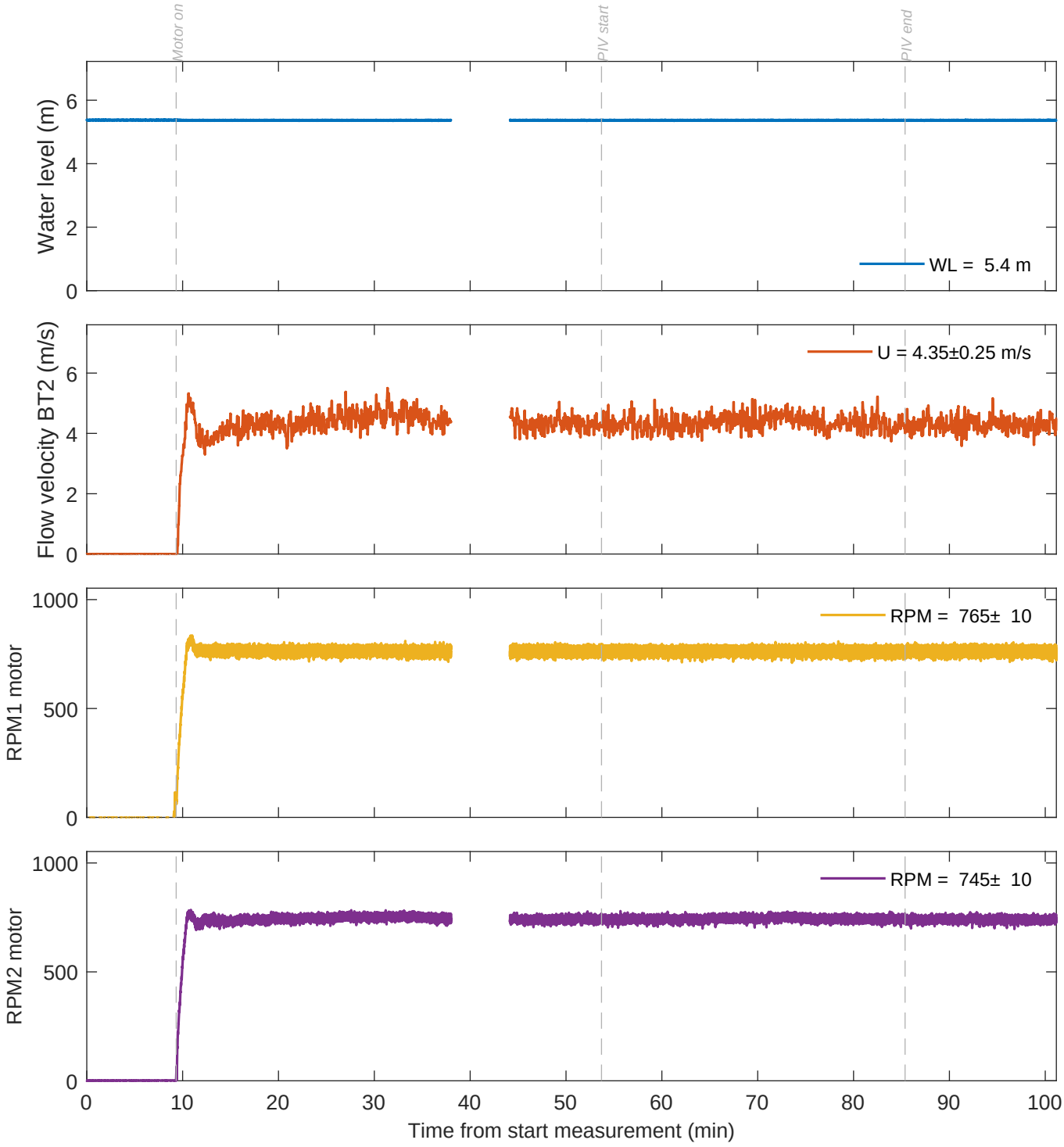
Water level, flow velocity BT2, RPM motor Active thruster: BT1&BT2 Δx = 0.8 m, Δy = -2.0 m, UKC = 2.5 m, U_{BT2} = 4.5 m/s	Measurement signals	TKI-SOP
	PIVSOP247	
Deltares	11206641	Fig. C



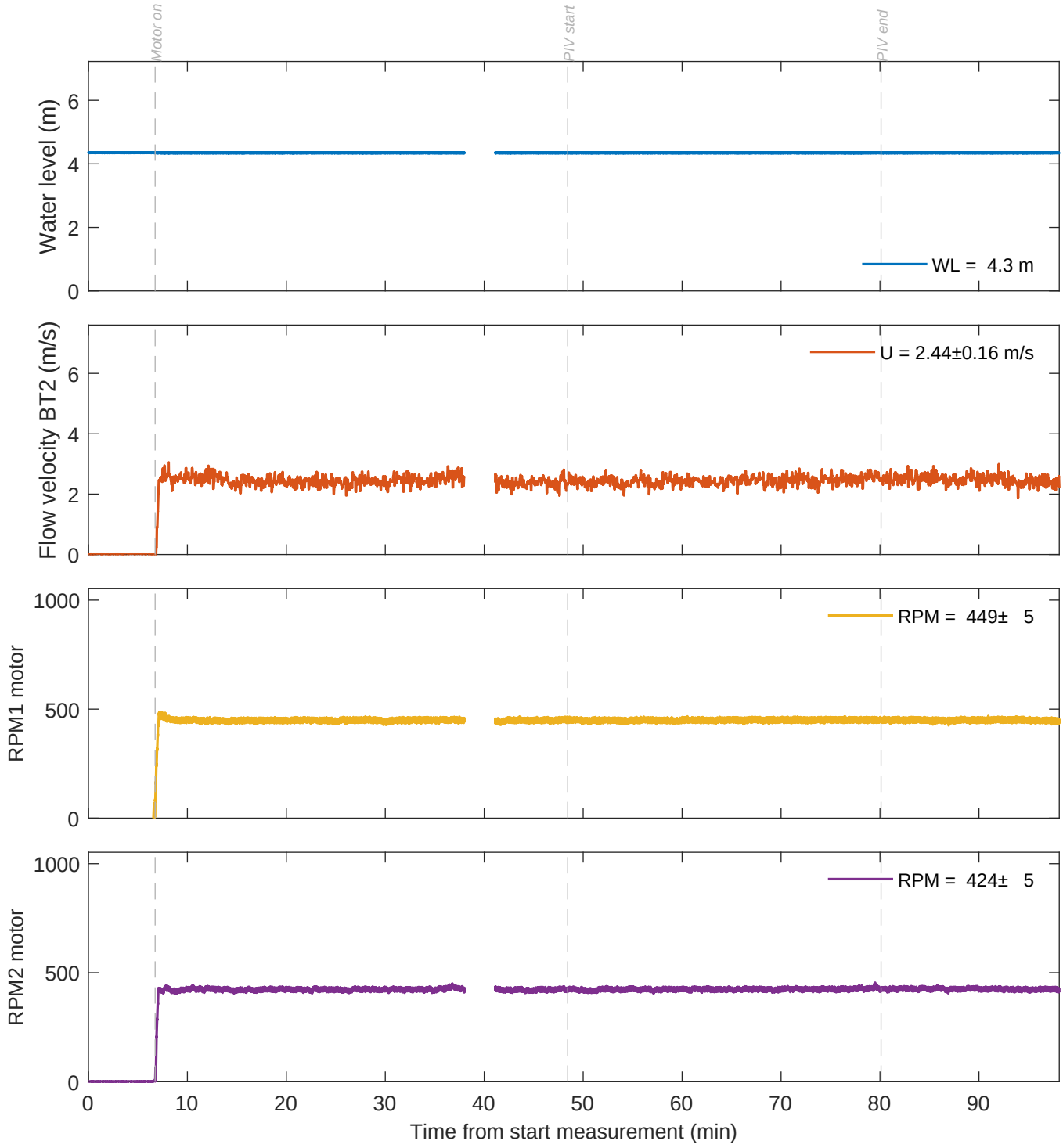
Water level, flow velocity BT2, RPM motor Active thruster: BT1&BT2 Δx = 0.8 m, Δy = -2.0 m, UKC = 2.5 m, U_{BT2} = 4.3 m/s	Measurement signals	TKI-SOP
	PIVSOP252	
Deltares	11206641	Fig. C



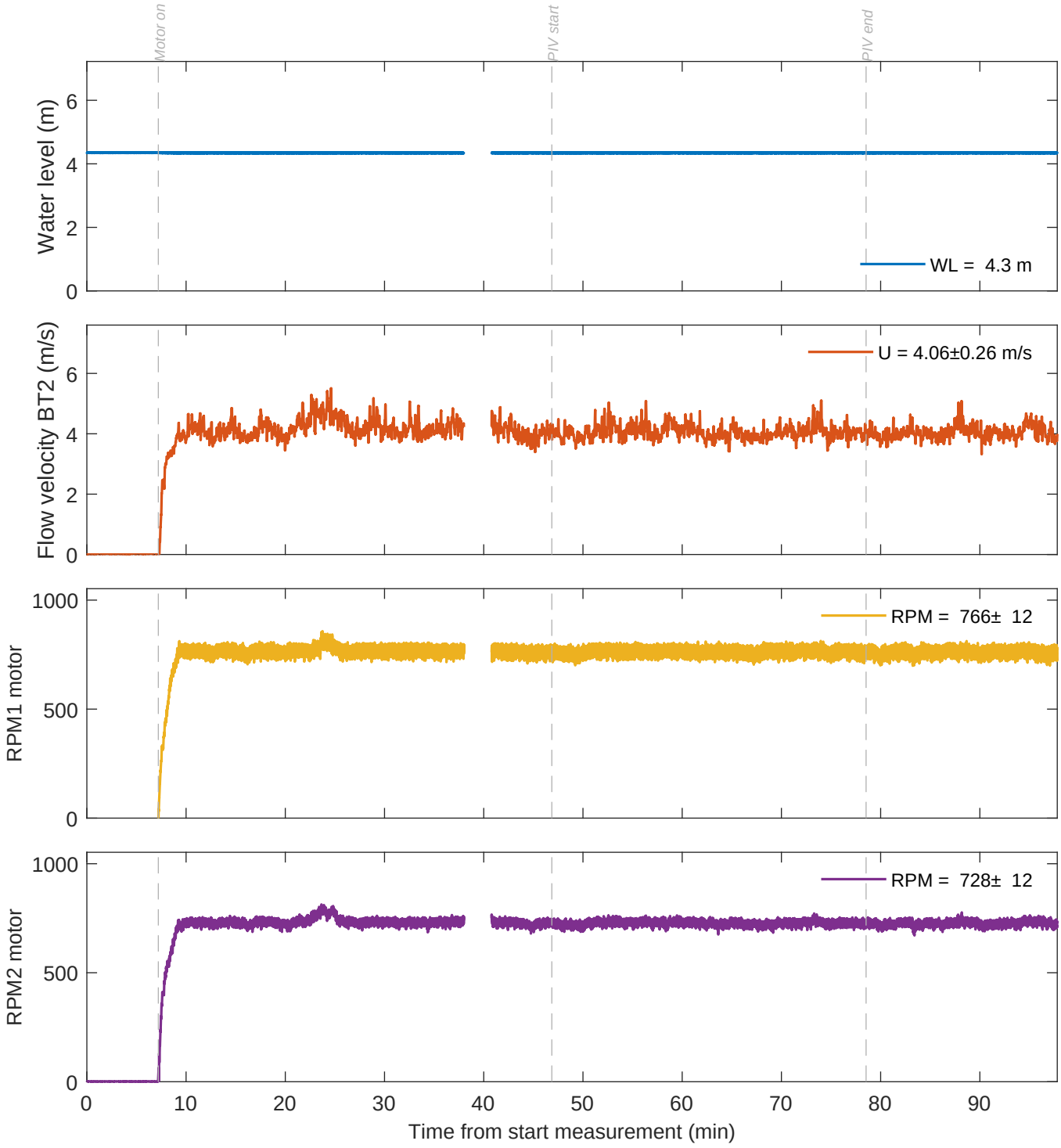
Water level, flow velocity BT2, RPM motor Active thruster: BT1&BT2 Δx = 3.0 m, Δy = 2.0 m, UKC = 2.5 m, U_{BT2} = 4.3 m/s	Measurement signals	TKI-SOP
	PIVSOP254	
Deltares	11206641	Fig. C



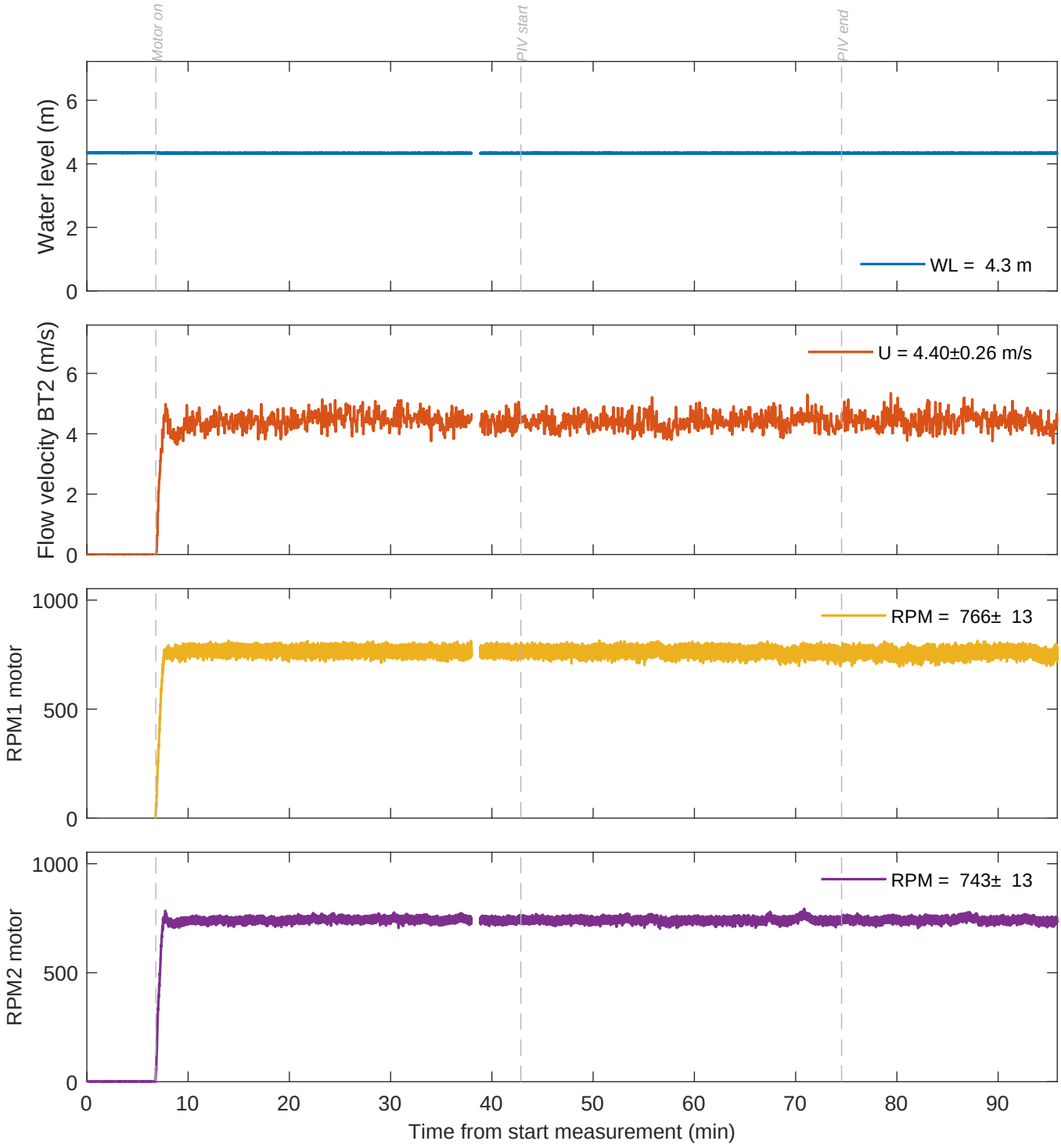
Water level, flow velocity BT2, RPM motor Active thruster: BT1&BT2 Δx = 0.8 m, Δy = 2.0 m, UKC = 1.5 m, U_{BT2} = 4.4 m/s	Measurement signals	TKI-SOP
	PIVSOP263	
Deltares	11206641	Fig. C



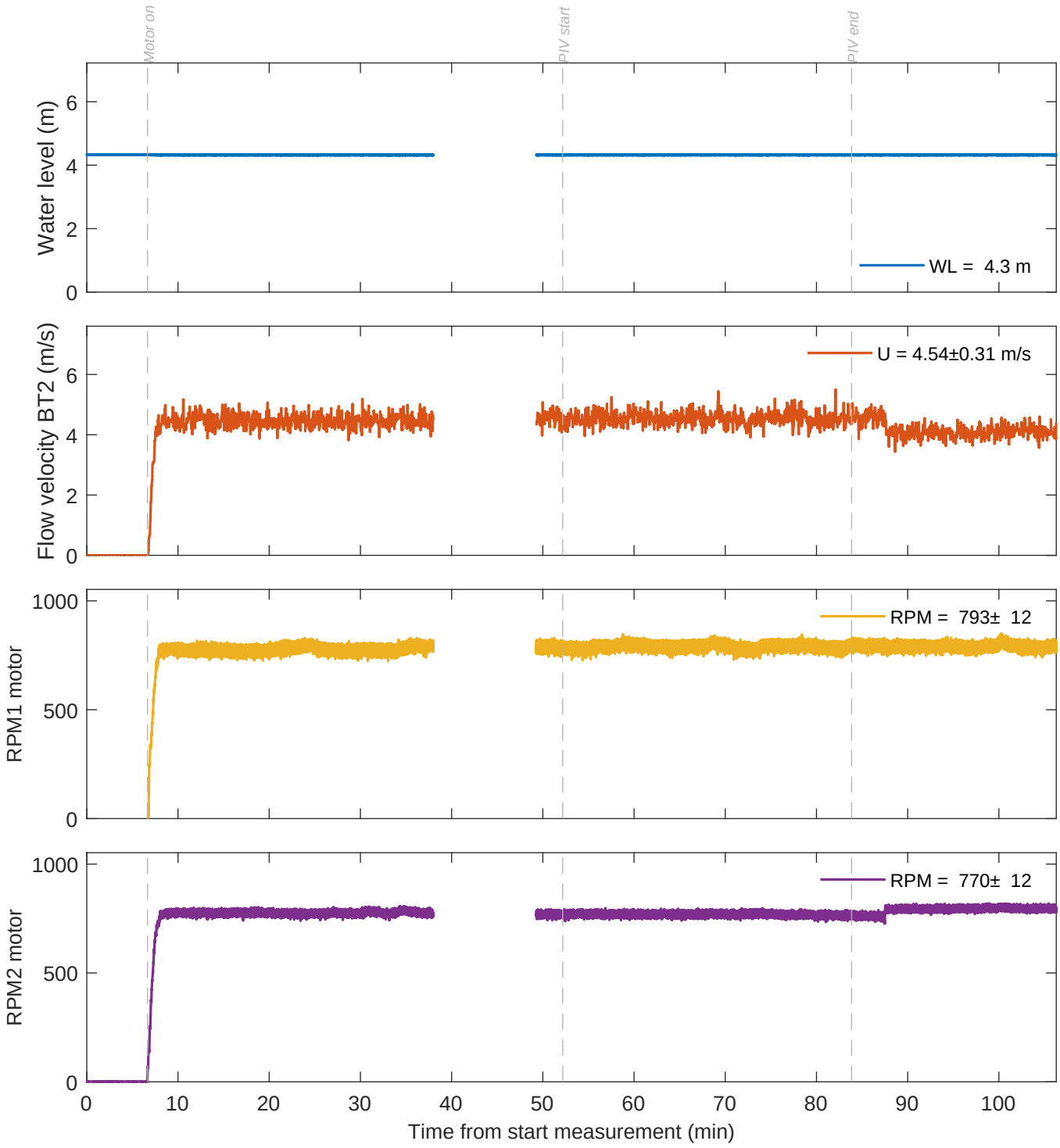
Water level, flow velocity BT2, RPM motor Active thruster: BT1&BT2 Δx = 0.8 m, Δy = 2.0 m, UKC = 0.4 m, U_{BT2} = 2.4 m/s	Measurement signals	TKI-SOP
	PIVSOP267	
Deltares	11206641	Fig. C



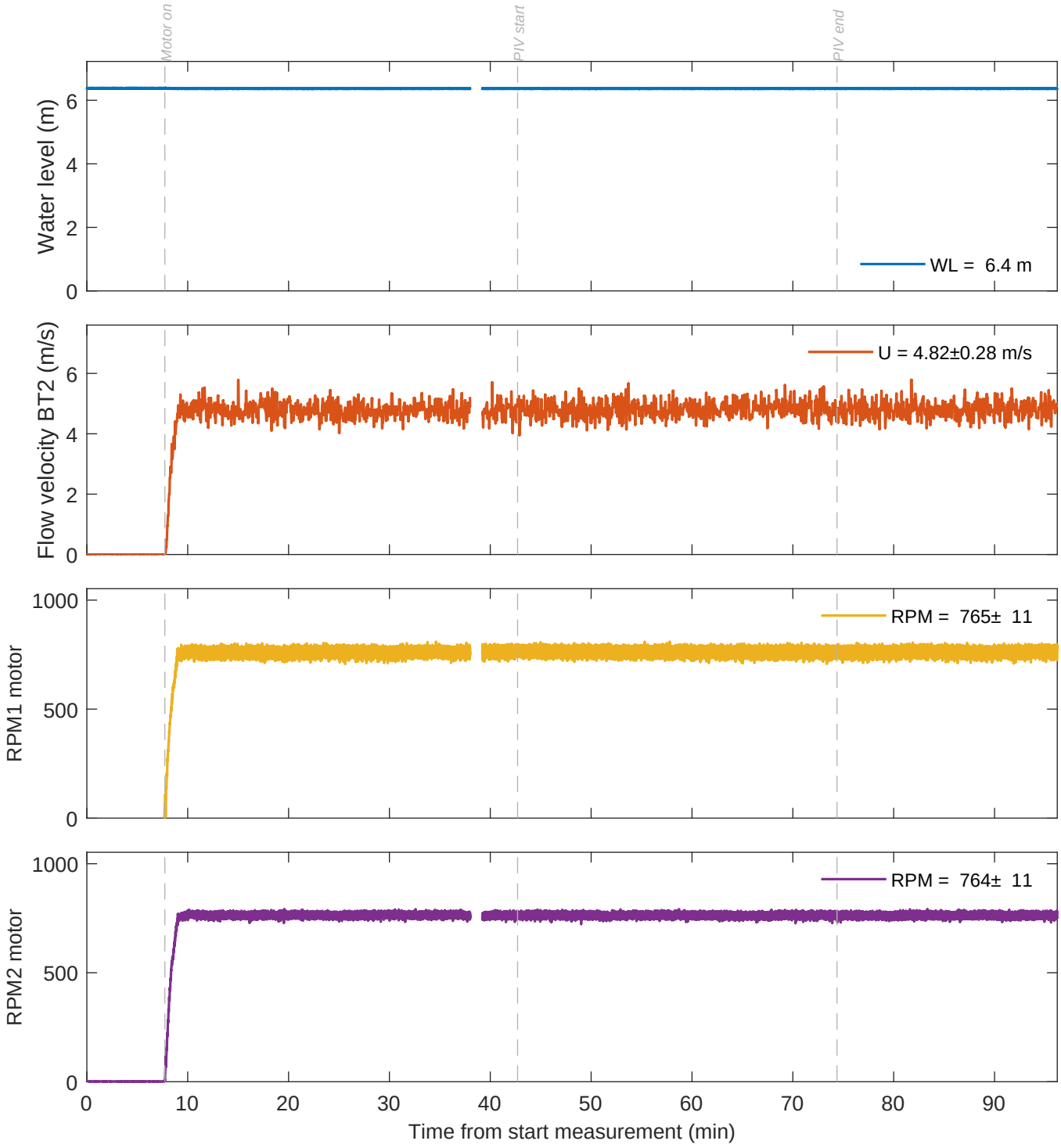
Water level, flow velocity BT2, RPM motor Active thruster: BT1&BT2 Δx = 0.8 m, Δy = 2.0 m, UKC = 0.4 m, U_{BT2} = 4.1 m/s	Measurement signals	TKI-SOP
	PIVSOP269	
Deltares	11206641	Fig. C



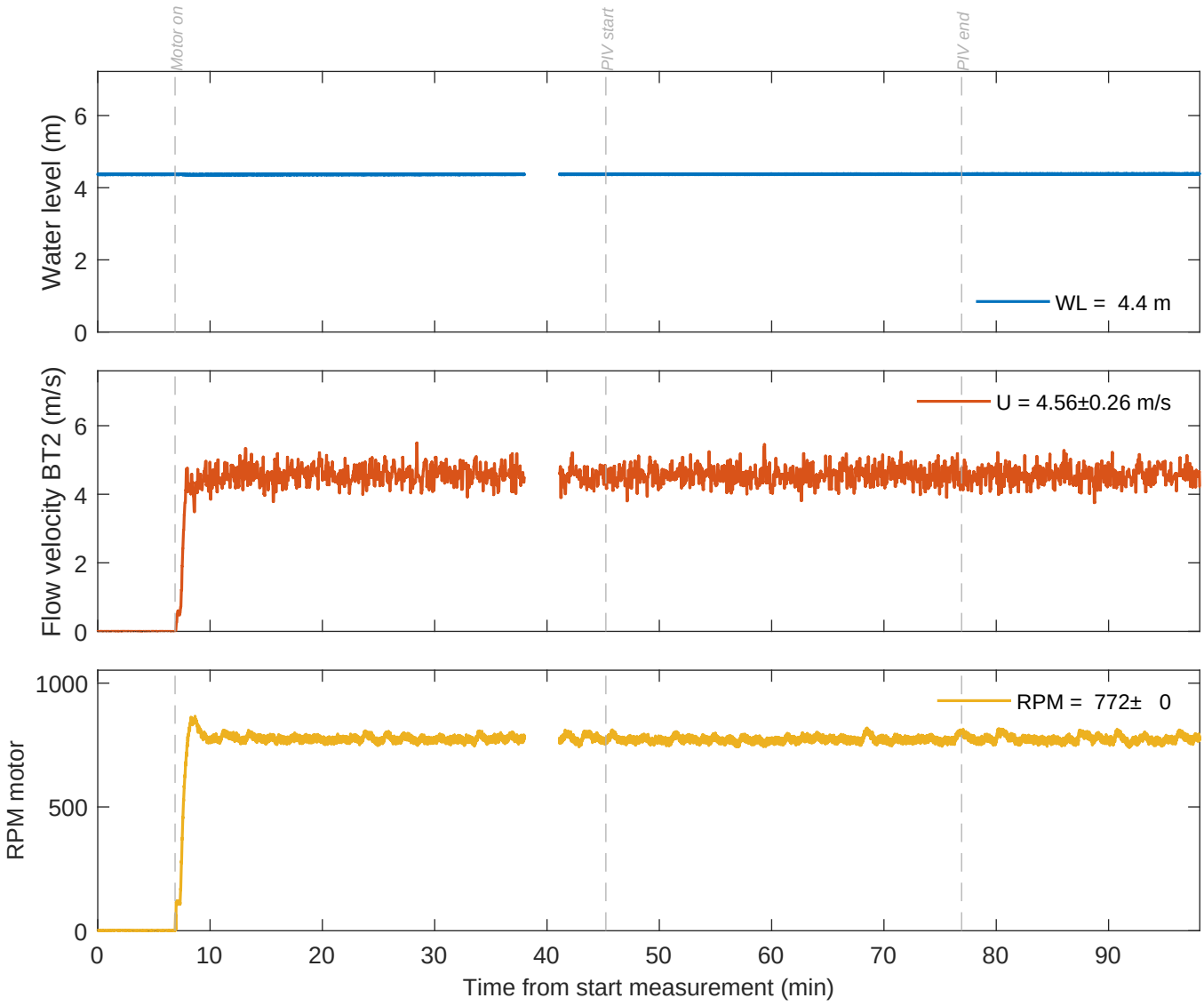
Water level, flow velocity BT2, RPM motor Active thruster: BT1&BT2 Δx = 3.0 m, Δy = 2.0 m, UKC = 0.4 m, U_{BT2} = 4.4 m/s	Measurement signals	TKI-SOP
	PIVSOP272	
Deltares	11206641	Fig. C



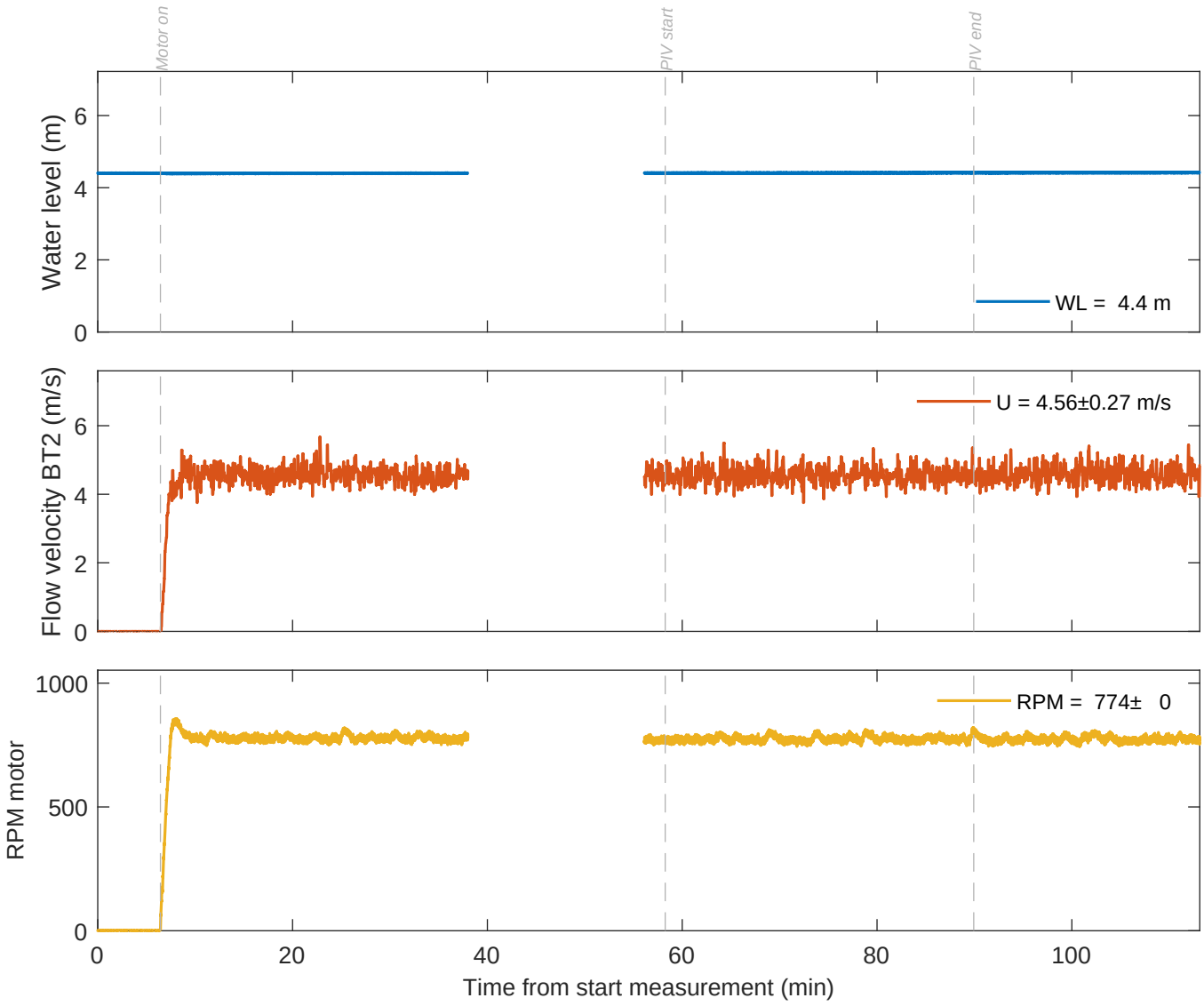
Water level, flow velocity BT2, RPM motor Active thruster: BT1&BT2 Δx = 23.1 m, Δy = 2.0 m, UKC = 0.4 m, U_{BT2} = 4.5 m/s	Measurement signals	TKI-SOP
	PIVSOP275	
Deltares	11206641	Fig. C



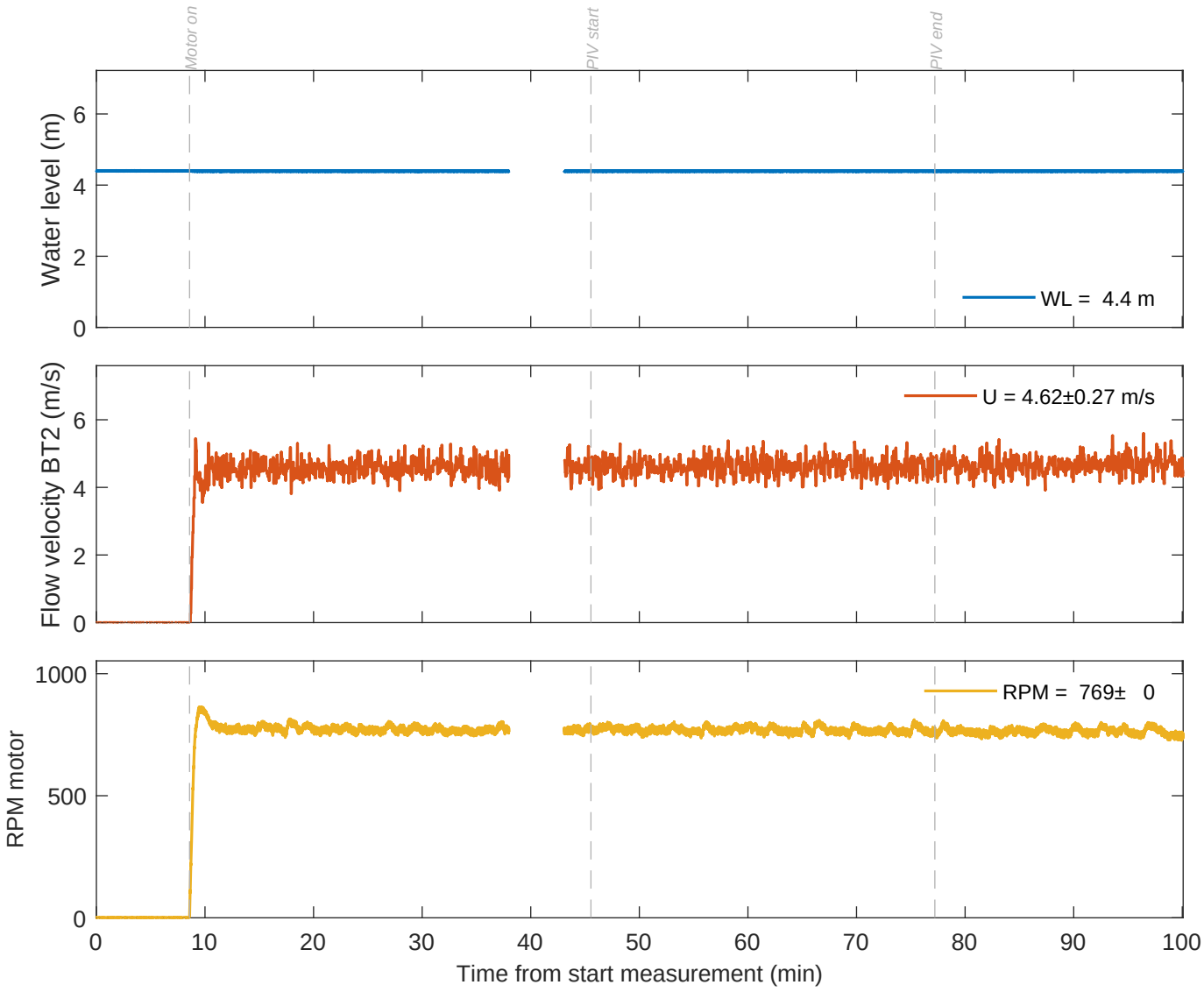
Water level, flow velocity BT2, RPM motor Active thruster: BT1&BT2 Δx = 23.1 m, Δy = 2.0 m, UKC = 2.5 m, U_{BT2} = 4.8 m/s	Measurement signals	TKI-SOP
	PIVSOP278	
Deltares	11206641	Fig. C



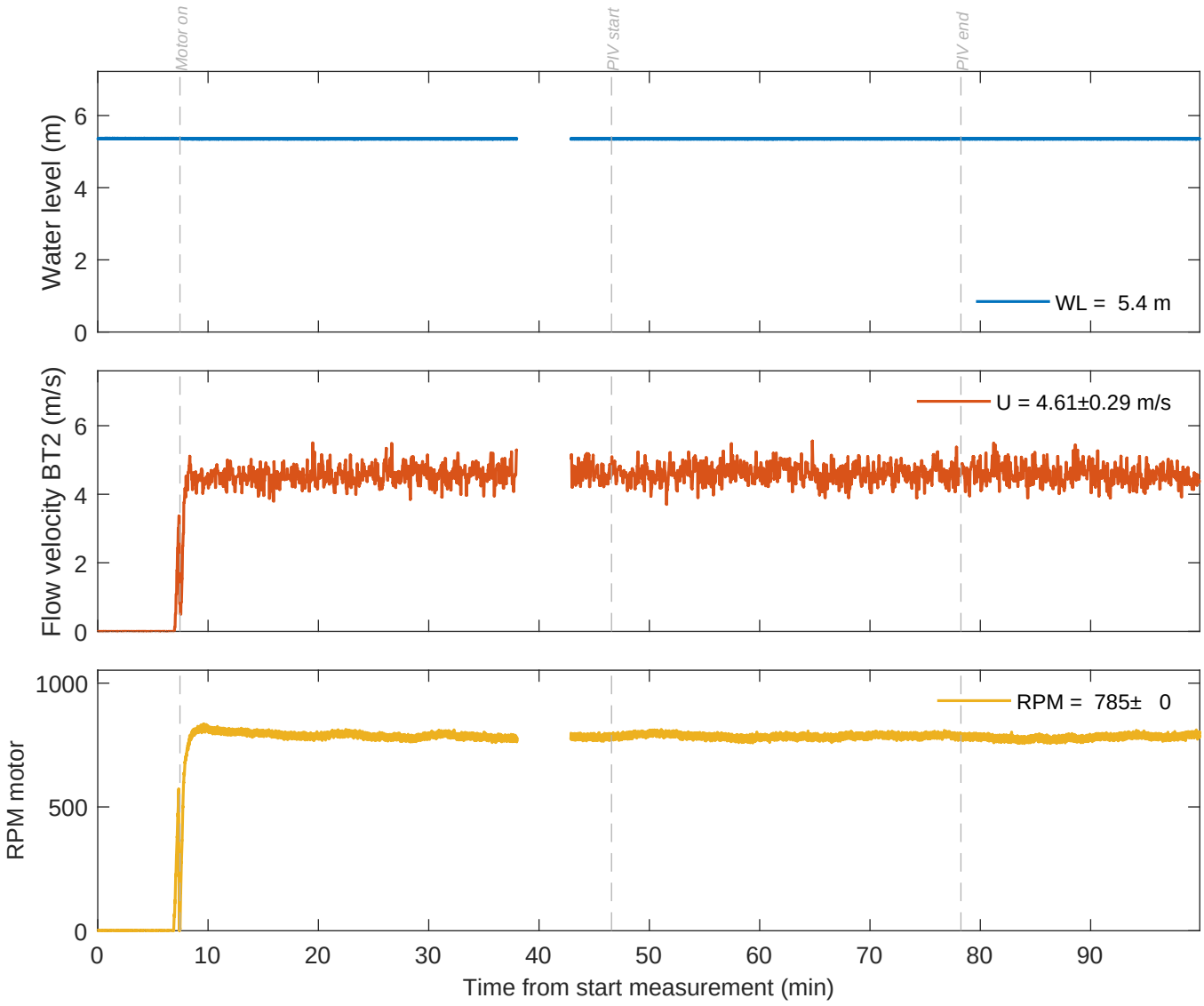
Water level, flow velocity BT2, RPM motor Active thruster: BT2 Δx = 0.8 m, Δy = 0.0 m, UKC = 0.4 m, U_{BT2} = 4.6 m/s	Measurement signals	TKI-SOP
	PIVSOP291	
Deltares	11206641	Fig. C



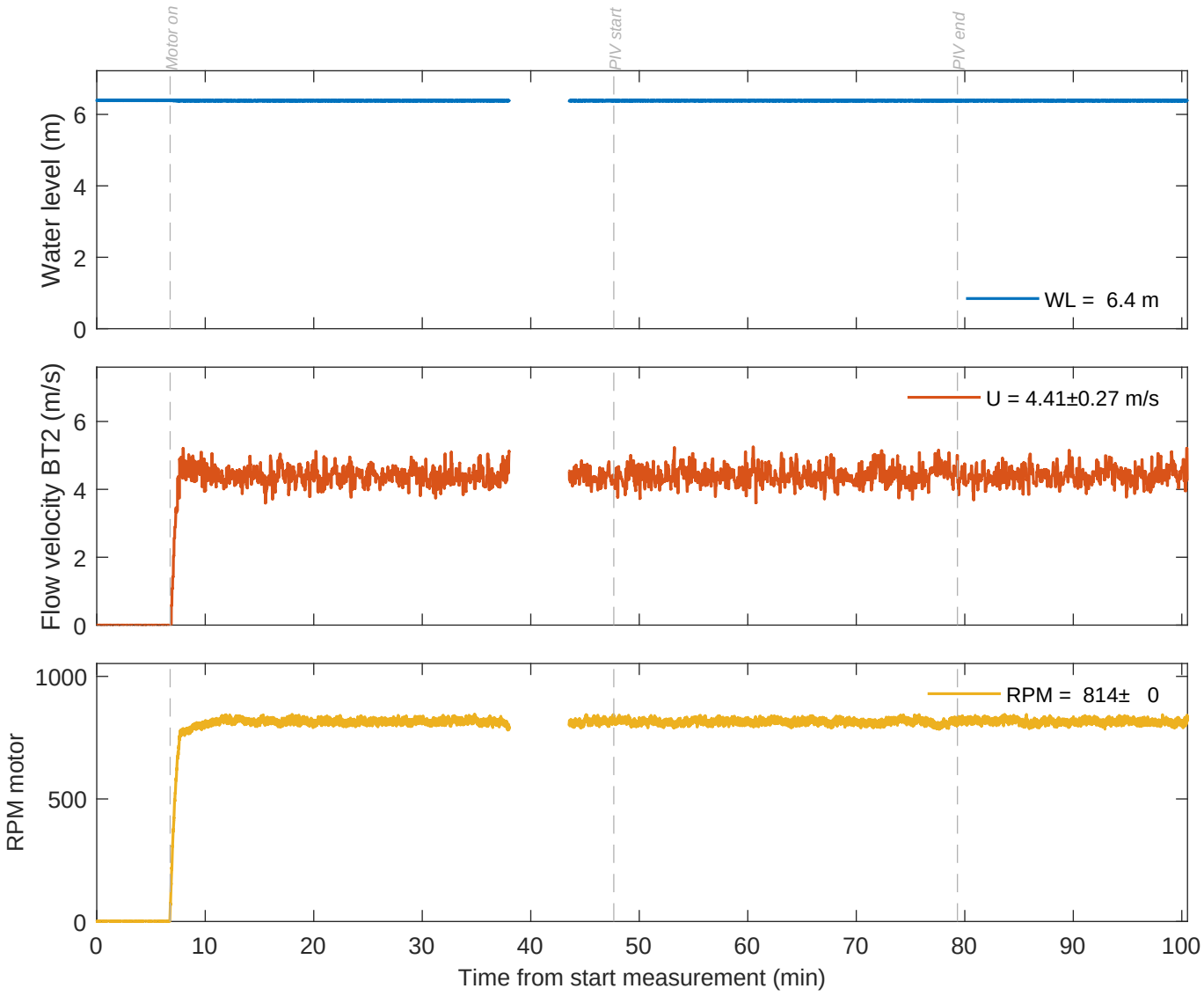
Water level, flow velocity BT2, RPM motor Active thruster: BT2 Δx = 0.8 m, Δy = -2.0 m, UKC = 0.4 m, U_{BT2} = 4.6 m/s	Measurement signals	TKI-SOP
	PIVSOP293	
Deltares	11206641	Fig. C



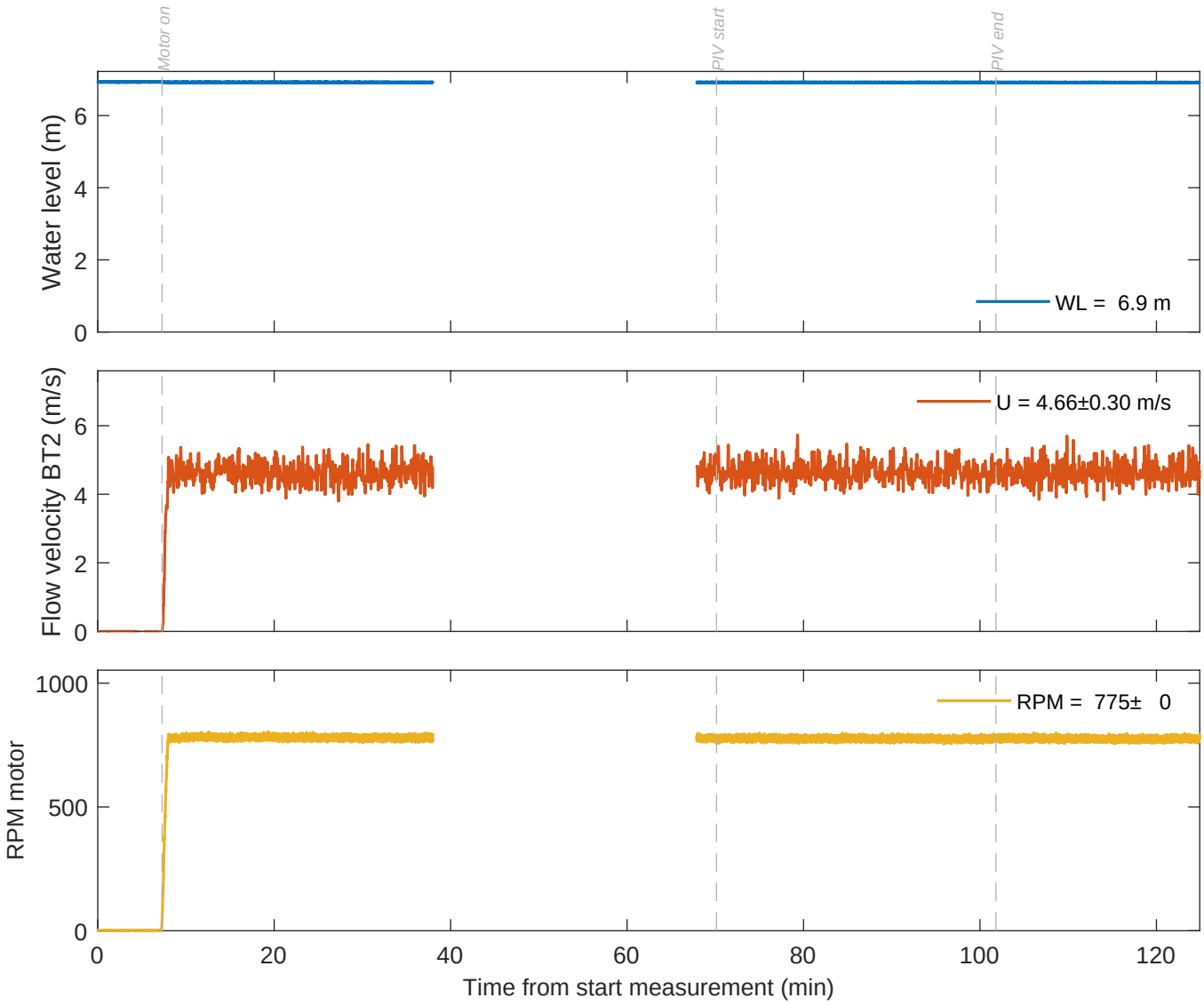
Water level, flow velocity BT2, RPM motor Active thruster: BT2 Δx = 0.8 m, Δy = -4.0 m, UKC = 0.4 m, U_{BT2} = 4.6 m/s	Measurement signals	TKI-SOP
	PIVSOP295	
Deltares	11206641	Fig. C



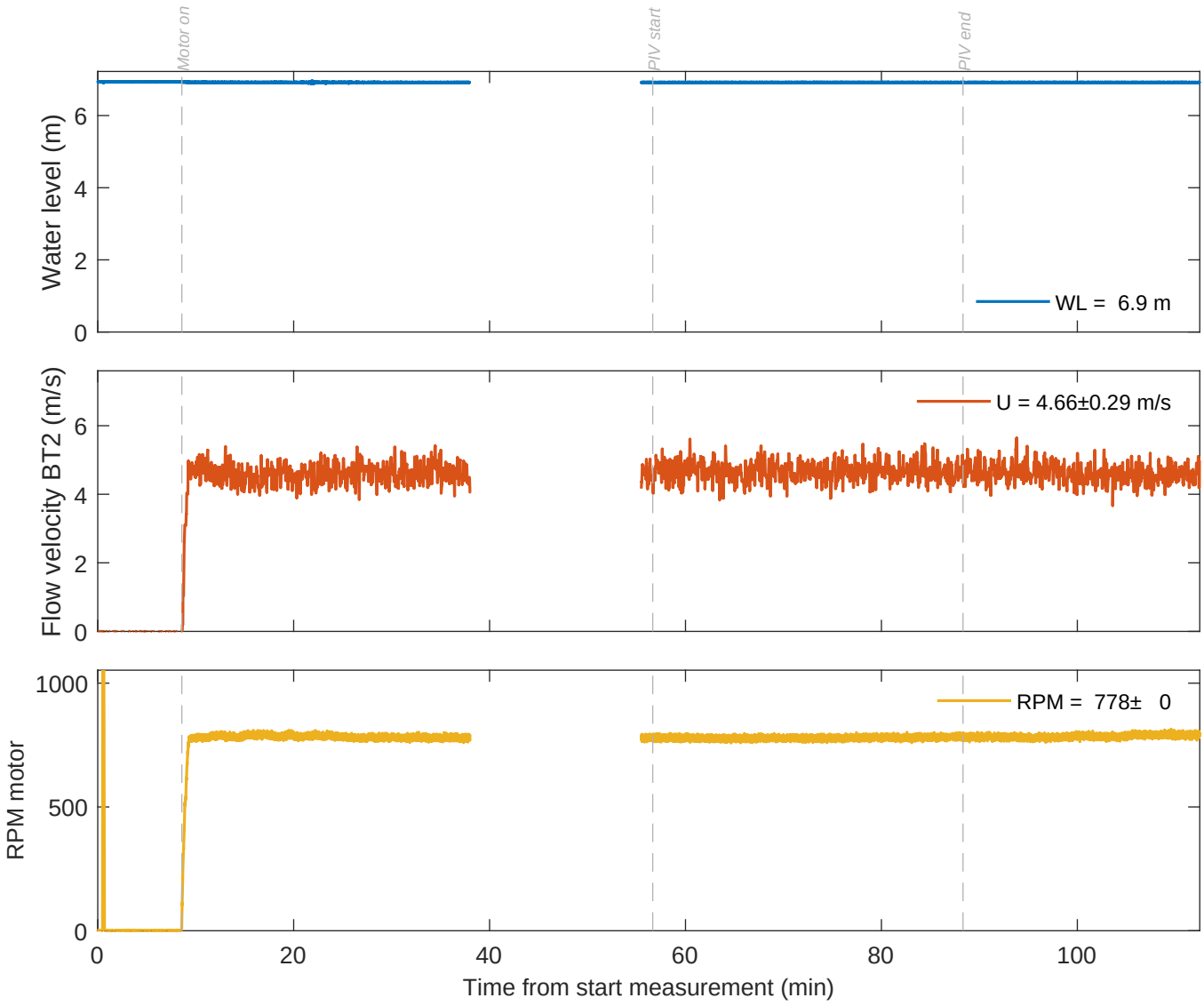
Water level, flow velocity BT2, RPM motor Active thruster: BT2 Δx = 0.8 m, Δy = 0.0 m, UKC = 1.4 m, U_{BT2} = 4.6 m/s	Measurement signals	TKI-SOP
	PIVSOP298	
Deltares	11206641	Fig. C



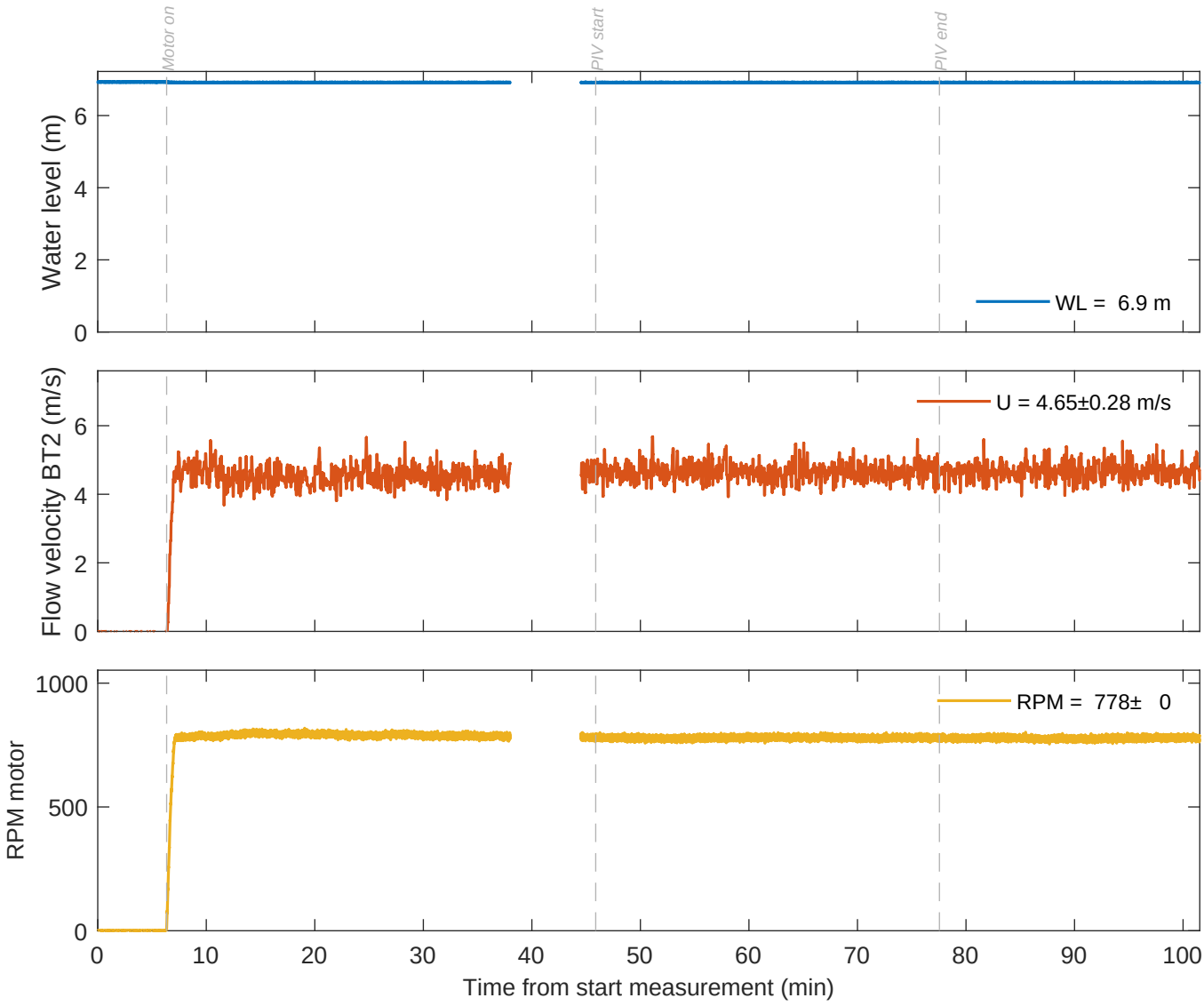
Water level, flow velocity BT2, RPM motor Active thruster: BT2 Δx = 0.8 m, Δy = 0.0 m, UKC = 2.4 m, U_{BT2} = 4.4 m/s	Measurement signals	TKI-SOP
	PIVSOP300	
Deltares	11206641	Fig. C



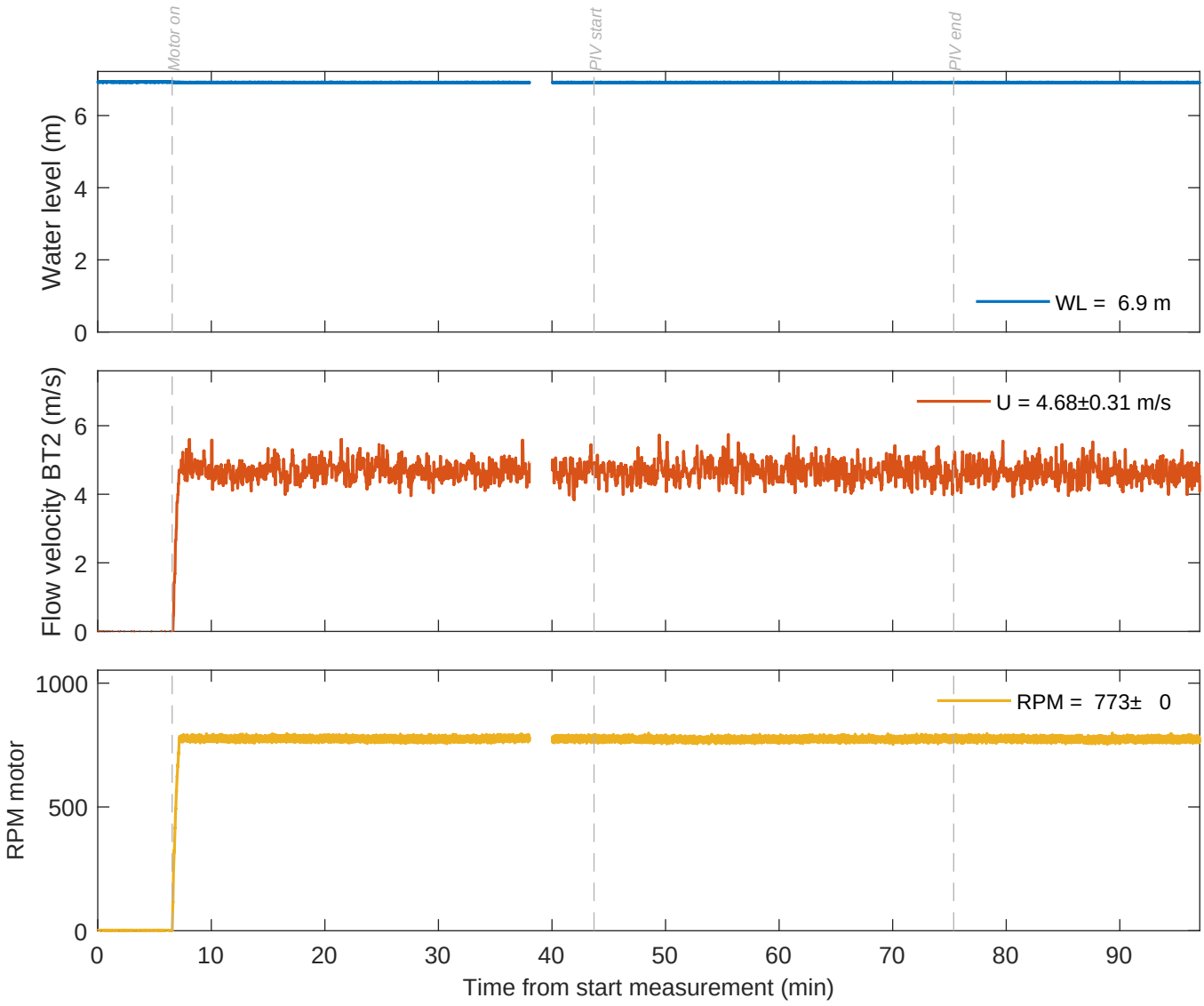
Water level, flow velocity BT2, RPM motor Active thruster: BT2 Δx = 0.8 m, Δy = 2.0 m, UKC = 2.5 m, U_{BT2} = 4.7 m/s	Measurement signals	TKI-SOP
	PIVSOP303	
Deltares	11206641	Fig. C



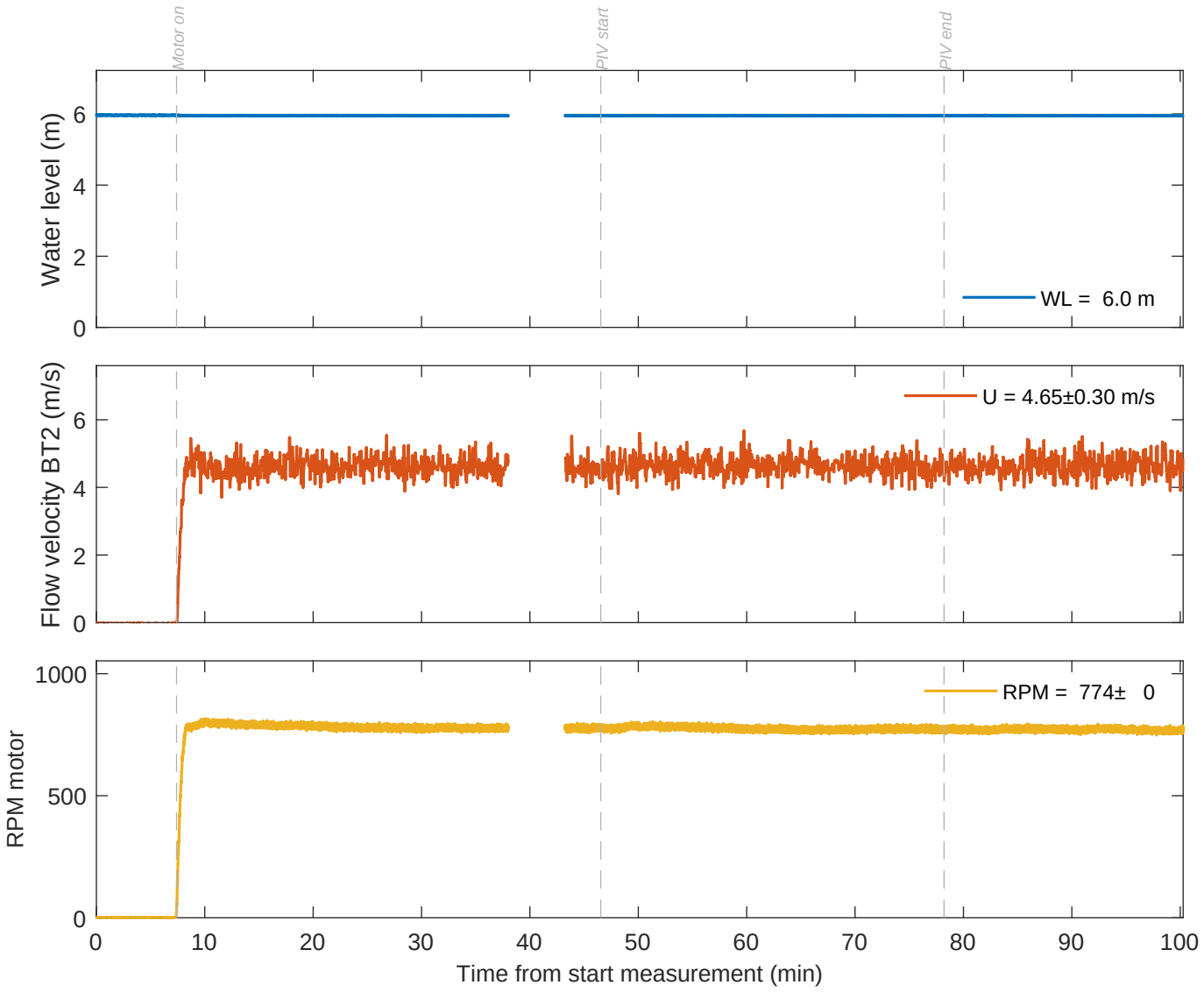
Water level, flow velocity BT2, RPM motor Active thruster: BT2 Δx = 0.8 m, Δy = -2.0 m, UKC = 2.5 m, U_{BT2} = 4.7 m/s	Measurement signals	TKI-SOP
	PIVSOP306	
Deltares	11206641	Fig. C



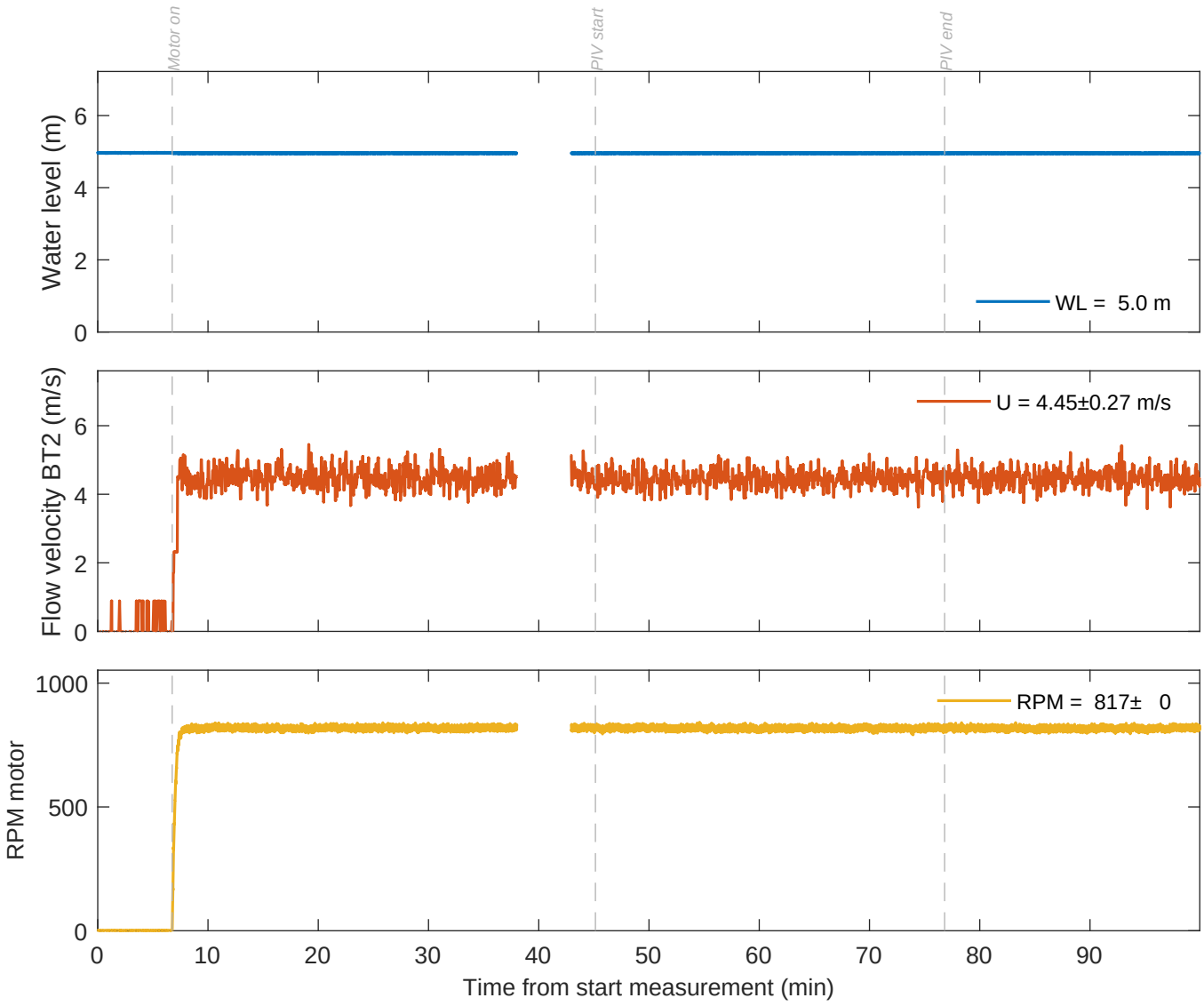
Water level, flow velocity BT2, RPM motor Active thruster: BT2 Δx = 0.8 m, Δy = 0.0 m, UKC = 2.5 m, U_{BT2} = 4.7 m/s	Measurement signals	TKI-SOP
	PIVSOP308	
Deltares	11206641	Fig. C



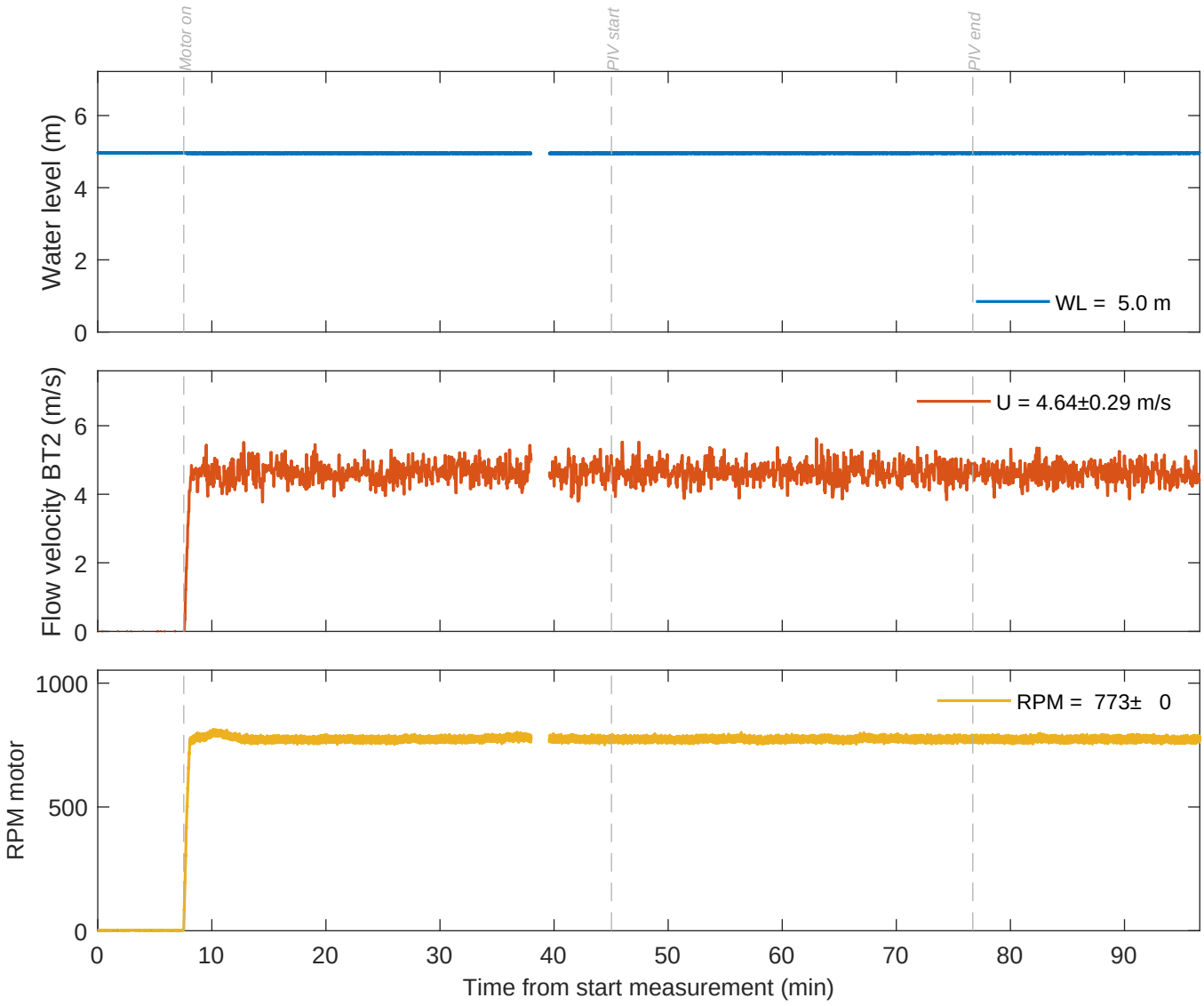
Water level, flow velocity BT2, RPM motor Active thruster: BT2 Δx = 3.0 m, Δy = 0.0 m, UKC = 2.5 m, U_{BT2} = 4.7 m/s	Measurement signals	TKI-SOP
	PIVSOP310	
Deltares	11206641	Fig. C



Water level, flow velocity BT2, RPM motor Active thruster: BT2 Δx = 0.8 m, Δy = 0.0 m, UKC = 1.4 m, U_{BT2} = 4.6 m/s	Measurement signals	TKI-SOP
	PIVSOP313	
Deltares	11206641	Fig. C



Water level, flow velocity BT2, RPM motor Active thruster: BT2 Δx = 0.8 m, Δy = 0.0 m, UKC = 0.4 m, U_{BT2} = 4.5 m/s	Measurement signals	TKI-SOP
	PIVSOP316	
Deltares	11206641	Fig. C



Water level, flow velocity BT2, RPM motor Active thruster: BT2 Δx = 3.0 m, Δy = 0.0 m, UKC = 0.4 m, U_{BT2} = 4.6 m/s	Measurement signals	TKI-SOP
	PIVSOP318	
Deltares	11206641	Fig. C