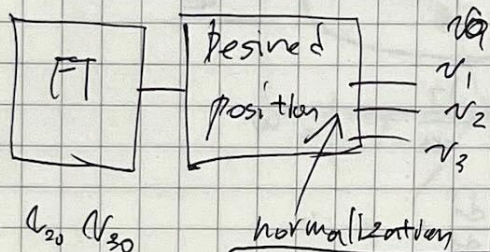
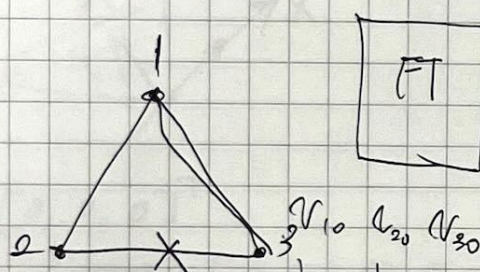


Units
Desired position

$$v_x = r \omega_x$$

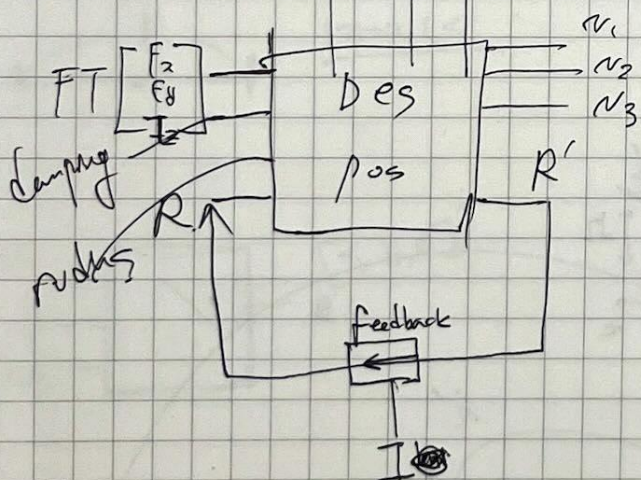


$$\frac{v_x}{r} dt = \omega_x dt = \theta_x$$

damping

$F_x \rightarrow$ TRANS

radians



$$R_2^0 = R_1^0 \underline{R_2^1}$$

$$= R_1^0 R_Y(\theta_2) R_X(\theta_3) R_Z(\theta_2)$$

$$= R_1^0 R_Y(\theta_2) R_{-X}(\theta_3) R_Z(\theta_2)$$

current frame rotation