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```
function euler_angles = DCM2Euler( seq_string, DCM )
%BmatEuler Turn an Euler Angle set into a B matrix
%   theta_dot_vec = B*body_rates_vec
fcnPrintQueue(mfilename('fullpath'))
euler_angles = zeros(3,1);

if strcmp(seq_string, '321')
    euler_angles(2) = asin(-DCM(1,3));
    euler_angles(1) = atan2(DCM(1,2),DCM(1,1));
    euler_angles(3) = atan2(DCM(2,3),DCM(3,3));
else
    fprintf('this rotation sequence is not supported');
end
end
```

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