DecompRMat - Decompose the rotation matrix into three angles.

Usage:
          [angz, angy, angx] = DecompRMat(R)

Input:
          R: 3x3 Rotation Matrix

Output:
          angz : angle about Z axis (in degree)
          angy : angle about Y axis (in degree)
          angx : angle about X axis (in degree)

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