$$\underline{v}_{P,1} = \underline{\omega}_1 \wedge \overrightarrow{AP}$$
$$\underline{v}_{Q,2} = v_2 \underline{j}$$
$$\underline{v}_{R,3} = \underline{\omega}_3 \wedge \overrightarrow{BR}$$

$$\sum\nolimits_1 \underline{v}_{C,2} = \underline{v}_{C,1} + v_{2,1}^{(rel)} \underline{\lambda} \qquad \underline{\lambda} = (\cos(\theta), \sin(\theta)) \quad (\theta < 0)$$
$$\sum\nolimits_3 \underline{v}_{D,1} = \underline{v}_{D,3} + v_{1,3}^{(rel)} \underline{\eta} \qquad \underline{\eta} = (\sin(\gamma), -\cos(\gamma)) \quad (\gamma > 0)$$

$$\omega_1 = \frac{v_2 \cos^2(\theta)}{d_2}$$

$$v_{2,1}^{(rel)} = v_2 \sin(\theta)$$

$$\omega_3 = \frac{\omega_1}{1 + \frac{d_1}{l_1} \frac{\sin(\gamma)}{\sin(\theta - \gamma)}}$$

$$v_{1,3}^{(rel)} = l_1 \frac{\sin(\theta)}{\sin(\gamma)} (\omega_3 - \omega_1)$$