

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

$$\begin{aligned}\sum_1 \underline{v}_{C,2} &= \underline{v}_{C,1} + v_{2,1}^{(rel)} \underline{\lambda} & \underline{\lambda} &= (\cos(\theta), \sin(\theta)) \quad (\theta < 0) \\ \sum_3 \underline{v}_{D,1} &= \underline{v}_{D,3} + v_{1,3}^{(rel)} \underline{\eta} & \underline{\eta} &= (\sin(\gamma), -\cos(\gamma)) \quad (\gamma > 0)\end{aligned}$$

$$\begin{aligned}\omega_1 &= \frac{v_2 \cos^2(\theta)}{d_2} \\ v_{2,1}^{(rel)} &= v_2 \sin(\theta) \\ \omega_3 &= \frac{\omega_1}{1 + \frac{d_1}{l_1} \frac{\sin(\gamma)}{\sin(\theta-\gamma)}} \\ v_{1,3}^{(rel)} &= l_1 \frac{\sin(\theta)}{\sin(\gamma)} (\omega_3 - \omega_1)\end{aligned}$$