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where  $v$  is a velocity vector for the bodies involved,  $J$  is a "Jacobian" matrix with one row for every degree of freedom the joint removes from the system, and  $c$  is a right hand side vector. At the next time step, a vector  $\lambda$  is calculated (of the same size as  $c$ ) such that the forces applied to the bodies to preserve the joint constraint are

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