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Lab Z - Prelab Answer Key
            L=T-V
                  = (=mpL2+8mpL2sh2(x)+=Tr)62+(=Jp++mpL2)22
                                             - zmpLpLrcos(a) O à - zmpLpgcos(x)
           30 = 2 mpLp (2 sin(x) cas(x)) 62 + 2 mpLpLr sin(x) 6 2 + 2 mpLp g sin(x)
= 1 mpLp sin(x) 62 + 2 mpLpLr sin(x) 6 2 + 2 mpLp g sin(x)
36 = (2 mpLr 2 + 8 mpLp 2 sin(x) + 2 Tr) (26) - 2 mpLpLr cos(x) 2
= (mpLr 2 + 4 mpLp 2 sin(x) + Tr) 6 - 2 mpLpLr cos(x) 2
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          = (= (=), + = mpLp2)(2à)-2mpLpL, cos(x) 0
          武(第)=(4mpLp2(2sn(x)cos(x)x))的+(mpL2+4mpL2sn2(x)+J)的
                                                          - 2mpLpLr(-sn/a) à - 2mpLpLr cos(x) à
                                      = 4mpLp sn(2a) & & + (mpLr2 + 4mpLp2 sn2(a) + Jr) & 
+ 2mpLpLr sin(a) à 2 - 2mpLpLr cos(a) à
         = (Jp+4mpL2) = - 2mpLpLr(-sn(a) a) 0 - 2mpLpLros(a) 0
                                    =(Jp+4mpL2) = + 2mpLpLy Sm(a) & - 2mpLpLy cos(a) B
  1. Q= 7-B, B
                          = 杂(器) - 治
                         = 4 mp Lp sn(20) di + (mp Lp + 4 mp Lp 2 sin 2(x)+ Jr) di
+ 2 mp Lp Lr sn(x) i 2 - 2 mp Lp Lr cos(x) i
2.0~=-8. 点 = 計(合意)- 意
                       = (Jp+ = mpLp2) = + = mpLp Lr sh(a) & - = mpLpLr cos(a) & - (= mpLp2 sin(Za) & + = mpLpLr sh(a) & a + = mpLpS sh(a))
                      = (Jp+4mpLp2) &-2mpLpLros(a) == = mpLp2 sn(2a) == ±mpLp3 sn(a)
```

3 Cartrollade: com steer system from my intent andition to any final andition Observable: con deduce system state from given autout.