```
function [angularAcceleration] = omegaDot_ip1ip1(rotation_iip1,omegaDot_ii,omega_ii, ↙
thetaDot,thetaDotDot)
% This function summarizes the angular acceleration at a joint from the
% previous link and the current link. Eqn. 6.46 in the textbook.
    arguments
        rotation_iip1 (3,3)
        omegaDot_ii (3,1)
        omega_ii (3,1)
        thetaDot
        thetaDotDot
    end

    angularAcceleration = rotation_iip1*omegaDot_ii + cross((rotation_iip1*omega_ii), ↙
(thetaDot*[0 0 1]')) + thetaDotDot*[0 0 1]';

end
```