

```
function [linearAccelCentroid] = vcDot_ip1lip1(omegaDot_ip1lip1,positionC_iip1, ω
omega_ip1lip1,vDot_ip1lip1)
% This function summarizes the linear acceleration of the centroid of joint from the
% previous link and the current link. Eqn. 6.48 in the textbook.
    arguments
        omegaDot_ip1lip1 (3,1)
        positionC_iip1 (3,1)
        omega_ip1lip1 (3,1)
        vDot_ip1lip1 (3,1)
    end

    linearAccelCentroid = cross(omegaDot_ip1lip1,positionC_iip1)+cross(omega_ip1lip1, ω
cross(omega_ip1lip1,positionC_iip1))+vDot_ip1lip1;

end
```