* i , a unit rector, errors as axis of robotion

 $\times \times$, ough of rotation, $X \in (0, 2\pi)$

Recoll the way eo, e, e, ez, ez were defined:

$$R_0 = \frac{x}{2}$$

$$R = \begin{bmatrix} R_1 \\ R_2 \\ R_3 \end{bmatrix} = \begin{bmatrix} u_1 \\ u_2 \\ u_3 \end{bmatrix} \cdot \sin \frac{x}{2} = u \cdot \sin \frac{x}{2}.$$

Now, if we have $p^{n+u} = -p \Rightarrow e^{u+w} = -e_0 = con \frac{\chi^{new}}{2}$

enew = - R = WAW Sing

$$\Rightarrow \frac{\chi^{N+W}}{2} = \overline{u} - \frac{\chi}{2} \Rightarrow \frac{\chi^{N+W}}{2} = 2\overline{u} - \chi$$

Then sin 2 400 = sin (a - \frac{7}{2}) = sin \frac{7}{2}

Therefore, using Eq. (1), (unew +u) sin $\chi = 0$ $\Rightarrow u^{*} = -u \cdot (\text{sin}(e \times e(0, 2\pi)))$