41514 – Dynamics of Machinery (week 2)
(Multibody Dynamics)

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Ilmar Santos
\[ T = \begin{bmatrix} \cos \theta & \sin \theta & 0 \\ 0 & 0 & 0 \\ \sin \theta & -\cos \theta & 0 \end{bmatrix} \]

\[ \begin{align*}
\Theta &= 0 \\
\begin{bmatrix}
\Theta(t) \\
\dot{\Theta}(t)
\end{bmatrix} \\
\omega &= \begin{bmatrix} 0 \\
0 \\
\dot{\Theta}
\end{bmatrix}
\end{align*} \]