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A 3-2-1 rotation from F. through yaw (), pitch (), and roll () angles: $R_{bi} = R_1()R_2()R_3()$ Reference Frames for Ship D&C (2) Illustration (from T. Fossen ' s Guidance and Control of Ocean Vehicles) shows relationship between intermediate axis systems and roll, pitch, and yaw, angles.

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Thor I. Fossen

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