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compute the added mass matrix and the damping matrix.

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A 3-2-1 rotation from F. i through yaw (), pitch (), and roll

() angles: $R_{bi} = R. 1() R. 2() R. 3()$

Reference Frames for Ship D&C (2)

Illustration (from T. Fos- sen ' s

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Thor I. Fossen

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robotic vehicles. First, guidance and motion forms including the maneuvering, path following, trajectory tracking, and position stabilization are described.

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