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5. Let $B_1 = B_0 + 5 B_0 v_0 = [9.5 \ 1.00 \ -1.50]^T$. The object's position in $\{A\}$ is $T_B A P_1 = A B T P_1 = [-4.89 \ 2.11 \ 3.60]$ 6. (2.1) $R = \text{rot}(\hat{Y}, \varphi) \text{rot}(\hat{Z}, \theta) \text{c}\varphi \ 0 \ s\varphi = 0 \ 1 \ 0 \ -s\varphi \ 0 \ \dots$

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Update, 4:07 p.m. EST/EDT: Craig Hershoff has reached out to us clarify that not only are the robot's motions more gentle than manually inserting a contact lens, but during the process, the user ...