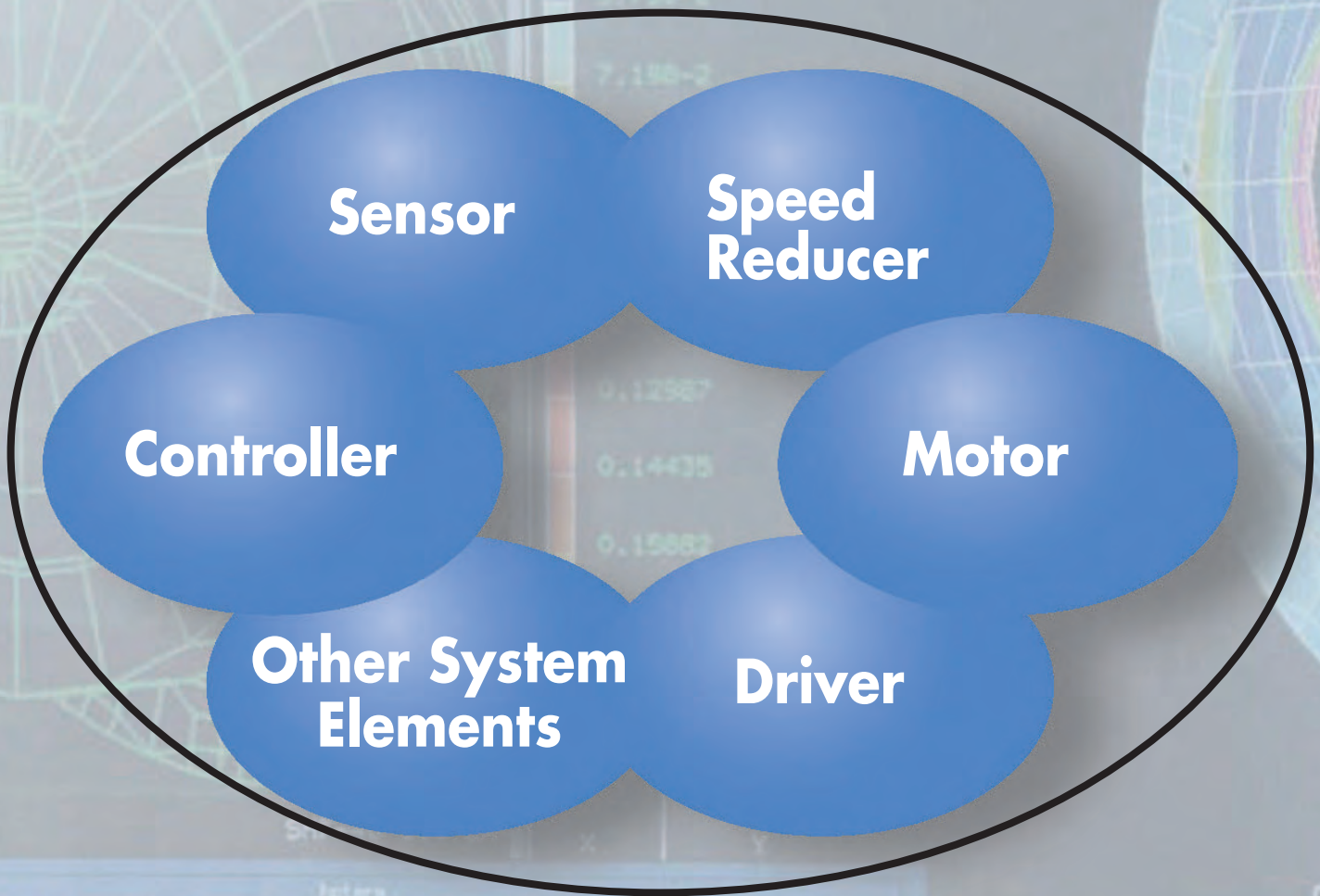


## Schematic Concept of Total Motion Control



```
txy**2.e2= 6*(txy**2.0 + tyz**2.0 + tzx**txy  
z**2.0 + tzx**2.0)  
se3 = sqrt(se1 + se2)  
se = 1.0 / sqrt( 2.0) * se3  
sige(j) = se I  
continue
```