Test Cases for Dynamics.py

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1. Test_zero_torque_rates_ideal_q: The disturbance and control torque are zero. Arbitrary position and velocity is set. Initial quaternion is [1,0,0,0] and angular rates are zero. Then qdot and wdot are zero.
2. Test_zero_torque_ideal_q: The disturbance and control torque are zero. Arbitrary position and velocity is set. Initial quaternion is [1,0,0,0] and angular rates are arbitrary. Then qdot is [0 , w].
3. Test_inertia_eigenvec: Set angular velocity as eigenvector of inertia matrix.Set all torques to zero. Then wdot is zero.
4. Test_kinematics_explicitly: The quaternion is set to be [0.4,0.254,-0.508,0.719319] and the angular velocity to be [0.1,-0.05,-0.3]. The explicit qdot is calculated to be [0.082498,0.114183,0.064066,-0.04095]. This is independent of disturbances.