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Title: IMU & Odom wrong in sim

Problem Encountered:

The odometry didn't correctly register the orientation of the vehicle. The problem was tracked back to the IMU's data.

Solution Implemented:

The actual problem turned out to be the simulation of the IMU, where the orientation quaternion was wrongly assumed to be euler angles, and so the x y z components were set to roll pitch yaw, making the rest of the computationwrong

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