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Readme file for qnv.py

Attitude Determination and Control Subsystem

quatDerBO(v_q,omega1))

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This function calculates derivative of error quaternion.

Input: quaternion which transforms orbit frame vector to body frame

omega1 which is equal to $v_q_BI_b + R * v_q_BO_b$ where R is rotation matrix corresponding to v_q_BO

Output: derivative of quaternion