Corey Marcus

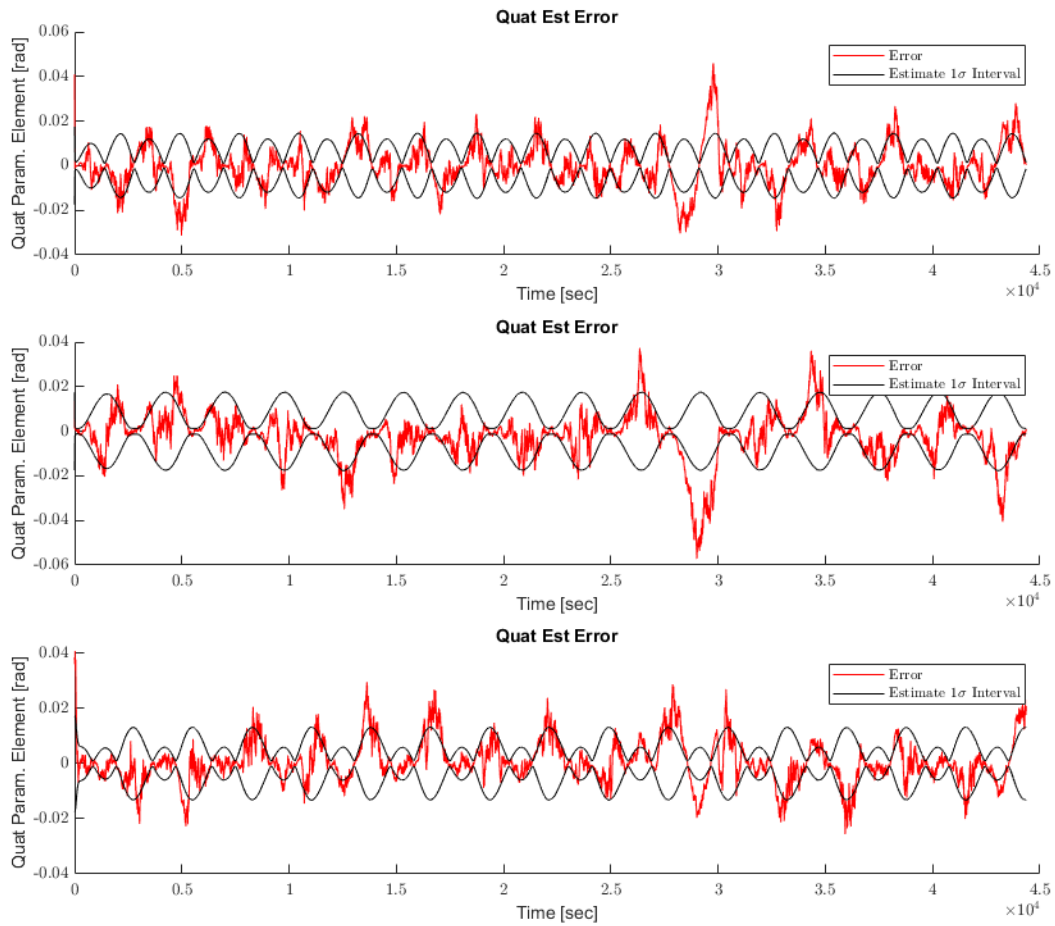**Satellite Control Systems**

Final Exam

The following graph shows attitude estimate errors. I chose double the vector component of the error quaternion as my error parameterization.

The next figure shows my bias estimate errors.