

Robot Dynamics

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github.com/silvasta/summary-rodyn



Contents

1 Kinematics	1
1.1 Vectors and Positions	1
1.2 Linear Velocity	1
1.3 Rotations	1
1.4 Angular Velocity	1
1.5 Parametrization of 3d rotations	1
1.6 Euler angles	1
1.7 angle axis and rotation vector	1
1.8 Unit Quaternions	1
1.9 Algebra with Quaternions	2
1.10 Time Derivatives and Rotational Velocity	2
1.11 Exercise 1b	2
2 Dynamics	2
3 Legged Robot	2
4 Rotorcraft	2
5 Fixed-Wing	2
1 Kinematics	
1.1 Vectors and Positions	
some definitions	
parametrizations	
1.2 Linear Velocity	
transformations	
1.3 Rotations	
- elementary rotations	
1.4 Angular Velocity	
1.5 Parametrization of 3d rotations	
1.6 Euler angles	
euler <> rotation matrix	
1.7 angle axis and rotation vector	
1.8 Unit Quaternions	
Quaternions <> rotation matrix	

1.9 Algebra with Quaternions

1.10 Time Derivatives and Rotational Velocity

1.11 Exercise 1b

$$\mathcal{I}\mathbf{w}_{\mathcal{E}} = \begin{bmatrix} \mathcal{I}\mathbf{v}_{\mathcal{E}} \\ \mathcal{I}\omega_{\mathcal{E}} \end{bmatrix}$$

2 Dynamics

3 Legged Robot

4 Rotorcraft

5 Fixed-Wing