

Robot Dynamics

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github.com/silvasta/summary-rodyn



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	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

$${}^{\mathcal{I}}\mathbf{w}_{\mathcal{E}} = \begin{bmatrix} {}^{\mathcal{I}}\mathbf{v}_{\mathcal{E}} \\ {}^{\mathcal{I}}\boldsymbol{\omega}_{\mathcal{E}} \end{bmatrix}$$

2 Dynamics

3 Legged Robot

4 Rotorcraft

5 Fixed-Wing