

### Rigid Body Motions

Skew- `skew(v)`

S-  
ymm-  
etric

Adjoint `tr2adjoint(T)`

Matrix

SO3 `SO3(<R>)`

SO3 `SO3.AngleAxis(theta, w_ha`

From `t)`

Angle-  
Axis

SO3 `SO3.RPY(<r>, <p>, <y>)`

From

RPY

SO3 `SO3.Raxis()`

From

Rx,

Ry, Rz

Angle- `SO3.angvec()`

Axis

From

SO3

SE3 `SE3(T)`

### Important Packages

Spatial Math (SO3, `spatialmath`

SE3...)

Basic Math (skew- `spatialmath.basic`

symmetric) `skewsymmetric`

# C

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Not published yet.

Last updated 27th December, 2023.

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