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$[r1\ r2\ r3] = \text{quat2angle}(q, s)$  calculates the set of rotation angles,  $r1$ ,  $r2$ ,  $r3$ , for a given quaternion,  $q$ , and a specified rotation sequence,  $s$ . The default rotation

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## **Quaternion to euler angle conversion for arbitrary rotation sequence**

e.g. if rotation sequence is 3-2-1,  $i_1$  is 3,  $i_2$  is 2, and  $i_3$  is 1 in Conversion of a quaternion to the equivalent Euler angles is a somewhat more complex

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Theorems 5.1 and 5.2 essentially define the two quaternion rotation operators which we will be using, while Theorems 5.3 and 5.4 tell how to handle sequences

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sequences and can quaternions themselves be further generalized to another Before giving a relationship of quaternions to rotations in.

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conversion of the quaternion to Euler angles. This is to enable quaternion to be compatible with other applications which use Euler rotation sequence to

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orthonormal coordinate frames can be related by a sequence of rotations (not more than three) about coordinate axes, where no two successive rotations may

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animation block (employs Euler rotation sequence of XYZ), which enables Keywords: Euler angles, Quaternion, Rotation Sequence, Matlab

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=T. Euler angle sequence. For example, consider first the Elementary Rotations (123 sequence). = = = The corresponding quaternions are: Roll, , About Pitch

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Another disadvantage of describing 3-dimensional rotations with rotation matrices is that the three axes of rotation, as well as the sequence of the rotations about

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