Robot Kinematics & Dynamics

METR 4202: **Robotics** & Automation

Dr Surya Singh -- Lecture # 3

August 9, 2017

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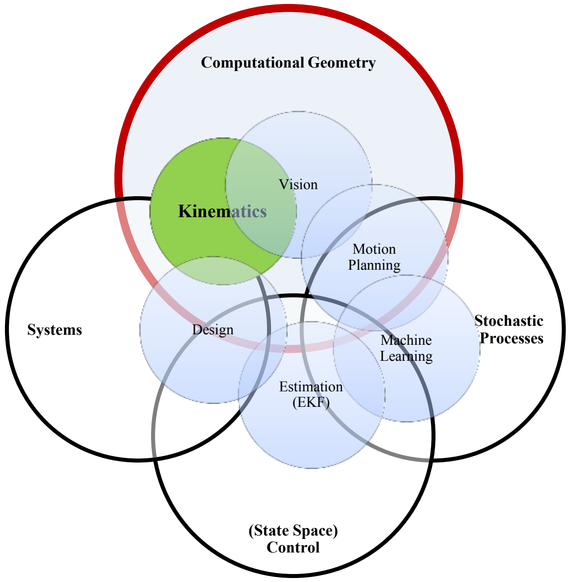
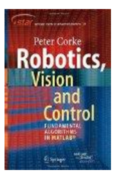
Lecture Schedule

Week	Date	Lecture (W: 3:05p-4:50, 7-222)
1	26-Jul	Introduction + Representing Position & Orientation & State
2	2-Aug	Robot Forward Kinematics (Frames, Transformation Matrices & Affine Transformations)
3	9-Aug	Robot Inverse Kinematics & Dynamics (Jacobeans)
4	16-Aug	*Ekka Day* (Robot Kinematics & Kinetics Review)
5	23-Aug	Robot Sensing: Perception & Linear Observers
6	30-Aug	Robot Sensing: Single View Geometry & Lines
7	6-Sep	Robot Sensing: Multiple View Geometry
8	13-Sep	Robot Sensing: Feature Detection
9	20-Sep	***Mid-Semester Exam***
	27-Sep	*Study break*
10	4-Oct	Motion Planning
11	11-Oct	Probabilistic Robotics: Localization & SLAM
12	18-Oct	Probabilistic Robotics: Planning & Control (State-Space/Shaping the Dynamic Response/LQR)
13	25-Oct	The Future of Robotics/Automation + Challenges + Course Review

Course Organization



Follow Along Reading:



[Robotics, Vision & Control](#)
by [Peter Corke](#)

Also online:[*SpringerLink*](#)

[UQ Library eBook: 364220144X](#)

Today

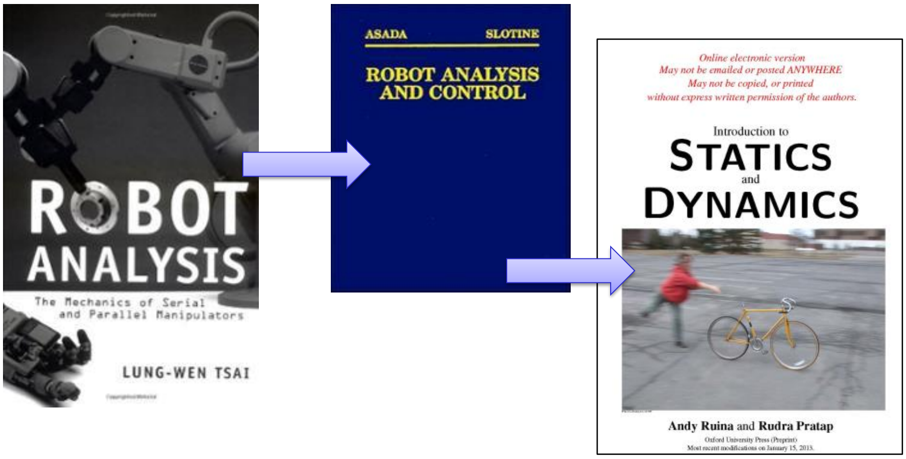
➔ Representing Space 🡸

- RVC
  - Chapter 7: Robot Arm Kinematics
  -

- Inverse Kinematics
  - RVC
    §7.3: Robot Arm Kinematics

Next Time

Reference Material



Online:
http://ruina.tam.cornell.edu/Book/RuinaPratap1-15-13.pdf

Space
A friendly reminder –Aug/21

$$\begin{bmatrix} Homogeneous \\ Coordinates \\ 0 \\ 1 \end{bmatrix}$$

Homogenous Coordinates

$$\hat{p} = \begin{bmatrix} \rho p_x & \rho p_y & \rho p_z & \rho \end{bmatrix}^T$$

- ρ is a scaling value

Homogenous Transformation

$$\begin{bmatrix} {}^{A}R_{B} & {}^{A}p \\ \gamma & \rho \end{bmatrix}$$

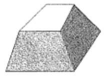
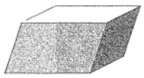
- γ is a projective transformation
- The Homogenous Transformation is a **linear operation** (even if projection is not)

Projective Transformations …

Group	Matrix	Distortion	Invariant properties
Projective 8 dof	$\begin{bmatrix} h_{11} & h_{12} & h_{13} \\ h_{21} & h_{22} & h_{23} \\ h_{31} & h_{32} & h_{33} \end{bmatrix}$		Concurrency, collinearity, **order of contact**: intersection (1 pt contact); tangency (2 pt contact); inflections (3 pt contact with line); tangent discontinuities and cusps. cross ratio (ratio of ratio of lengths).
Affine 6 dof	$\begin{bmatrix} a_{11} & a_{12} & t_x \\ a_{21} & a_{22} & t_y \\ 0 & 0 & 1 \end{bmatrix}$		Parallelism, ratio of areas, ratio of lengths on collinear or parallel lines (e.g. midpoints), linear combinations of vectors (e.g. centroids). The line at infinity, $\mathbf{l}_\infty$.
Similarity 4 dof	$\begin{bmatrix} sr_{11} & sr_{12} & t_x \\ sr_{21} & sr_{22} & t_y \\ 0 & 0 & 1 \end{bmatrix}$		Ratio of lengths, angle. The circular points, $\mathbf{I}, \mathbf{J}$ (see section 2.7.3).
Euclidean 3 dof	$\begin{bmatrix} r_{11} & r_{12} & t_x \\ r_{21} & r_{22} & t_y \\ 0 & 0 & 1 \end{bmatrix}$		Length, area

p.44, R. Hartley and A. Zisserman. *Multiple View Geometry in Computer Vision*

Projective Transformations & Other Transformations of 3D Space

Group	Matrix	Distortion	Invariant properties
Projective 15 dof	$\begin{bmatrix} A & t \\ v^T & v \end{bmatrix}$		Intersection and tangency of surfaces in contact. Sign of Gaussian curvature.
Affine 12 dof	$\begin{bmatrix} A & t \\ 0^T & 1 \end{bmatrix}$		Parallelism of planes, volume ratios, centroids. The plane at infinity, π_∞, (see section 3.5).
Similarity 7 dof	$\begin{bmatrix} sR & t \\ 0^T & 1 \end{bmatrix}$		The absolute conic, Ω_∞, (see section 3.6).
Euclidean 6 dof	$\begin{bmatrix} R & t \\ 0^T & 1 \end{bmatrix}$		Volume.

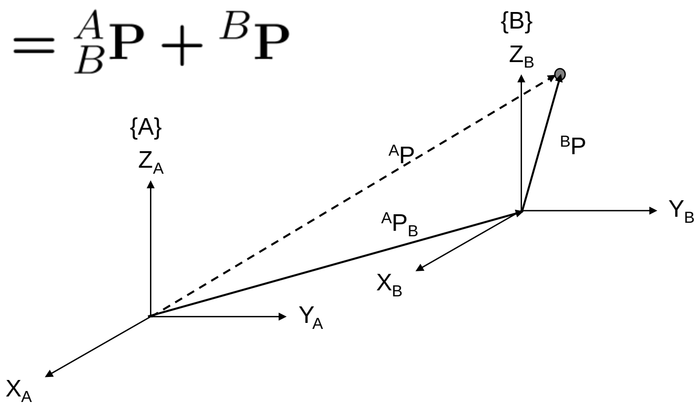
p.78, R. Hartley and A. Zisserman. *Multiple View Geometry in Computer Vision*

Coordinate Transformations [1]

- Translation Again:

  If {B} is translated with respect to {A} **without rotation**, then it is a vector sum

$$^{A}\mathbf{P} = {}^{A}_{B}\mathbf{P} + {}^{B}\mathbf{P}$$

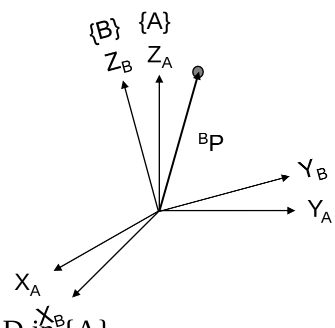


Coordinate Transformations [2]

- Rotation Again:
  {B} is rotated with respect to {A} then
  use rotation matrix to determine new components

- NOTE: $${}^{A}\mathbf{P} = {}^{A}_{B}\mathbf{R}\,{}^{B}\mathbf{P}$$
  - The Rotation matrix's ***subscript*** matches the position vector's **superscript**

$${}^{A}\mathbf{P} = {}^{A}_{[\![B]\!]}\mathbf{R}\,{}^{[\![B]\!]}\mathbf{P}$$

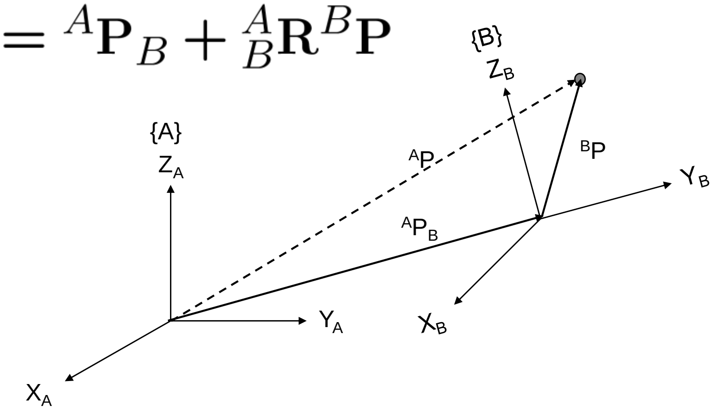


  - This gives Point Positions of {B} ORIENTED in {A}

Coordinate Transformations [3]

- Composite transformation:
  {B} is moved with respect to {A}:

$${}^{A}\mathbf{P} = {}^{A}\mathbf{P}_{B} + {}^{A}_{B}\mathbf{R}\,{}^{B}\mathbf{P}$$



General Coordinate Transformations [1]

- A compact representation of the translation and rotation is known as the **Homogeneous Transformation**

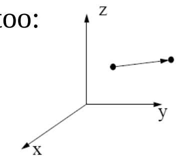
$$ {}^{A}_{B}\mathbf{T} = \begin{bmatrix} & {}^{A}_{B}\mathbf{R} & & {}^{A}\mathbf{P}_{B} \\ 0 & 0 & 0 & 1 \end{bmatrix} $$

- This allows us to cast the rotation and translation of the general transform in a single matrix form

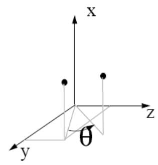
$$ \begin{bmatrix} {}^{A}\mathbf{P} \\ 1 \end{bmatrix} = {}^{A}_{B}\mathbf{T} \begin{bmatrix} {}^{B}\mathbf{P} \\ 1 \end{bmatrix} $$

General Coordinate Transformations [2]

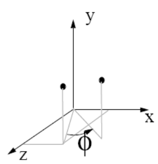
- Similarly, fundamental orthonormal transformations can be represented in this form too:



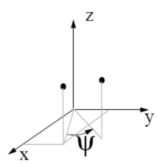
$$ Trans(u, v, w) = \begin{bmatrix} 1 & 0 & 0 & u \\ 0 & 1 & 0 & v \\ 0 & 0 & 1 & w \\ 0 & 0 & 0 & 1 \end{bmatrix} $$



$$ Rotx(\theta) = \begin{bmatrix} 1 & 0 & 0 & 0 \\ 0 & c\theta & -s\theta & 0 \\ 0 & s\theta & c\theta & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix} $$



$$ Roty(\phi) = \begin{bmatrix} c\phi & 0 & s\phi & 0 \\ 0 & 1 & 0 & 0 \\ -s\phi & 0 & c\phi & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix} $$

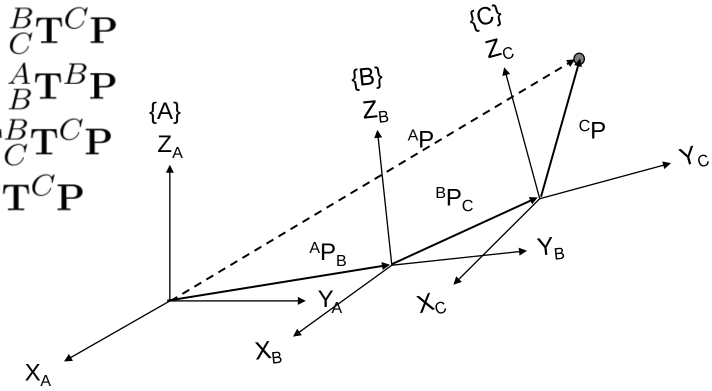


$$ Rotz(\psi) = \begin{bmatrix} c\psi & -s\psi & 0 & 0 \\ s\psi & c\psi & 0 & 0 \\ 0 & 0 & 1 & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix} $$

General Coordinate Transformations [3]

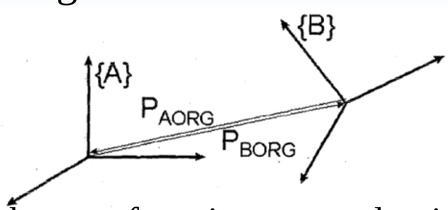
- Multiple transformations compounded as a chain

$$
\begin{aligned}
{}^B\mathbf{P} &= {}^B_C\mathbf{T}\,{}^C\mathbf{P} \\
{}^A\mathbf{P} &= {}^A_B\mathbf{T}\,{}^B\mathbf{P} \\
&= {}^A_B\mathbf{T}\,{}^B_C\mathbf{T}\,{}^C\mathbf{P} \\
&= {}^A_C\mathbf{T}\,{}^C\mathbf{P}
\end{aligned}
$$



$$
{}^A_C\mathbf{T} = \left[\begin{array}{cc} {}^A_B\mathbf{R}\,{}^B_C\mathbf{R} & {}^A\mathbf{P}_B + {}^A_B\mathbf{R}\,{}^B\mathbf{P}_C \\ 0 \quad 0 \quad 0 & 1 \end{array}\right]
$$

Inverse of a Homogeneous Transformation Matrix



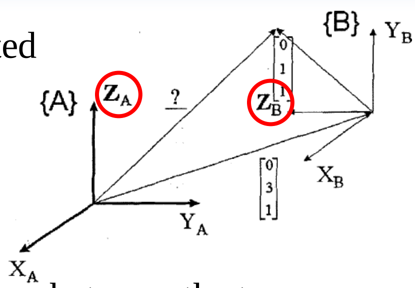
- The inverse of the transform is **not** equal to its transpose because this 4×4 matrix is not orthonormal ($T^{-1} \neq T^T$)
- Invert by parts to give:

$$
{}^A_BT = \begin{bmatrix} {}^A_BR & {}^A\mathbf{p}_{Borg/O_A} \\ 0 \quad 0 \quad 0 & 1 \end{bmatrix}
$$

$$
{}^A_BT^{-1} = {}^B_AT = \begin{bmatrix} {}^A_BR^T & -{}^A_BR^T\,{}^A\mathbf{p}_{Borg/O_A} \\ 0 \quad 0 \quad 0 & 1 \end{bmatrix} = \begin{bmatrix} {}^B_AR & {}^B\mathbf{p}_{Aorg/O_B} \\ 0 \quad 0 \quad 0 & 1 \end{bmatrix}
$$

Tutorial Problem

The origin of frame *{B}* is translated to a position [0 3 1] with respect to frame *{A}*.



We would like to find:

1. The homogeneous transformation between the two frames in the figure.
2. For a point *P* defined as as [0 1 1] in frame *{B}*, we would like to find the vector describing this point with respect to frame *{A}*.

Tutorial Solution

• The matrix ${}_BT^A$ is formed as defined earlier:

• Since P in the frame is:

• We find vector **p** in frame *{A}* using the relationship

➔

- The matrix ${}_BT^A$ is formed as defined earlier:

$$ {}^A_BT = \begin{bmatrix} 1 & 0 & 0 & 0 \\ 0 & 0 & -1 & 3 \\ 0 & 1 & 0 & 1 \\ 0 & 0 & 0 & 1 \end{bmatrix} $$

- Since P in the frame is: $ {}^B\mathbf{p} = \begin{bmatrix} 0 \\ 1 \\ 1 \\ 1 \end{bmatrix} $

- We find vector **p** in frame *{A}* using the relationship

$$ {}^Ap = {}^A_BT\,{}^Bp $$

➔ $ {}^A\mathbf{p} = \begin{bmatrix} 0 \\ 2 \\ 2 \\ 1 \end{bmatrix} $

Forward

Kinematics

→ → → →

Forward Kinematics [1]

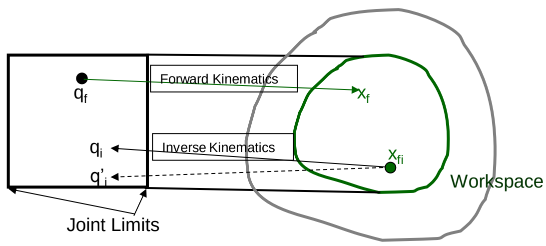
- Forward kinematics is the process of chaining homogeneous transforms together. For example to:
  - Find the articulations of a mechanism, or
  - the fixed transformation between two frames which is known in terms of linear and rotary parameters.
- Calculates the final position from the **machine** (**joint variables**)
- Unique for an open kinematic chain (**serial arm**)
- "Complicated" (multiple solutions, etc.) for a closed kinematic chain (**parallel arm**)

Forward Kinematics [2]

- Can think of this as "spaces":
  - Workspace (x,y,z,α,β,γ): The robot's position & orientation
  - Joint space ($\theta_1 \ldots \theta_n$): A state-space vector of joint variables

$$\vec{\mathbf{x}} = \begin{bmatrix} \vec{\mathbf{p}} \\ \vec{\Theta} \end{bmatrix}$$

$$\vec{\mathbf{q}} = \begin{bmatrix} q_1 \\ \vdots \\ q_n \end{bmatrix}$$

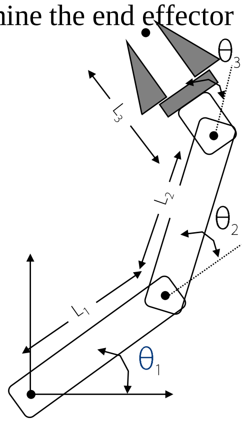


Forward Kinematics [3]

- Consider a planar RRR manipular
- Given the joint angles and link lengths, we can determine the end effector pose:

$$x = L_1 \cos\theta_1 + L_2 \cos(\theta_1 + \theta_2) + \ldots$$
$$L_3 \cos(\theta_1 + \theta_2 + \theta_3)$$

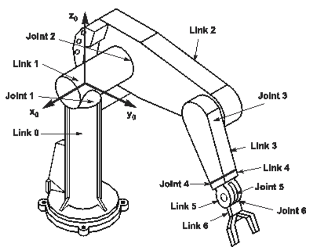
$$y = L_1 \sin\theta_1 + L_2 \sin(\theta_1 + \theta_2) + \ldots$$
$$L_3 \sin(\theta_1 + \theta_2 + \theta_3)$$

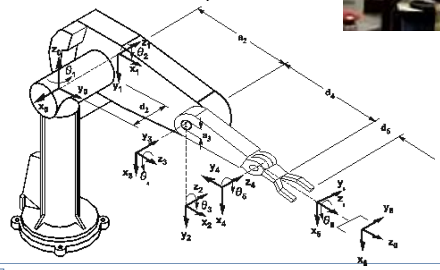


- This isn't too difficult to determine for a simple, planar manipulator. BUT …

Forward Kinematics [4]: The PUMA 560!

- What about a more complicated mechanism?





Denavit Hartenberg [DH] Notation

- J. Denavit and R. S. Hartenberg first proposed the use of homogeneous transforms for articulated mechanisms

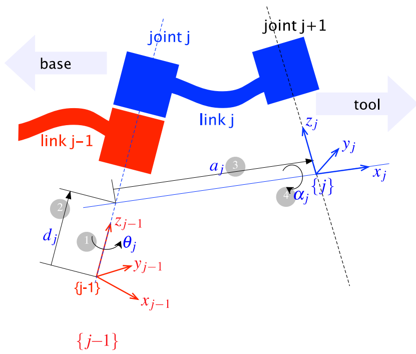
  (But B. Roth, introduced it to robotics)

- A kinematics "short-cut" that reduced the number of parameters by adding a structure to frame selection

- For two frames positioned in space, the first can be moved into coincidence with the second by a sequence of 4 operations:
  - rotate around the x_{i-1} axis by an angle α_i
  - translate along the x_{i-1} axis by a distance a_i
  - translate along the new z axis by a distance d_i
  - rotate around the new z axis by an angle θ_i

Denavit-Hartenberg Convention

- link length a_i the offset distance between the z_{i-1} and z_i axes along the x_i axis;
- link twist α_i the angle from the z_{i-1} axis to the z_i axis about the x_i axis;



Art c/o P. Corke

- link offset d_i the distance from the origin of frame i-1 to the x_i axis along the z_{i-1} axis;
- joint angle θ_i the angle between the x_{i-1} and x_i axes about the z_{i-1} axis.

DH: Where to place frame?

1. Align an axis along principal motion
   1. Rotary (**R**): align rotation axis along the z axis
   2. Prismatic (**P**): align slider travel along x axis

2. Orient so as to position x axis towards next frame

3. $\theta_{\text{(rot } z)} \rightarrow d_{\text{(trans } z)} \rightarrow a_{\text{(trans } x)} \rightarrow \alpha_{\text{(rot } x)}$

Denavit-Hartenberg → Rotation Matrix

- Each transformation is a product of 4 “basic” transformations (instead of 6)

$$
\begin{aligned}
{}^{i-1}A_i =& Rot_{z,\theta_i} Trans_{z,d_i} Trans_{x,a_i} Rot_{x,\alpha_i} \\
=& \begin{bmatrix} c_{\theta_i} & -s_{\theta_i} & 0 & 0 \\ s_{\theta_i} & c_{\theta_i} & 0 & 0 \\ 0 & 0 & 1 & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix}
\begin{bmatrix} 1 & 0 & 0 & 0 \\ 0 & 1 & 0 & 0 \\ 0 & 0 & 1 & d_i \\ 0 & 0 & 0 & 1 \end{bmatrix}
\begin{bmatrix} 1 & 0 & 0 & a_i \\ 0 & 1 & 0 & 0 \\ 0 & 0 & 1 & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix} \cdots \\
& \begin{bmatrix} 1 & 0 & 0 & 0 \\ 0 & c_{\alpha_i} & -s_{\alpha_i} & 0 \\ 0 & s_{\alpha_i} & c_{\alpha_i} & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix} \\
=& \begin{bmatrix} c_{\theta_i} & -s_{\theta_i} c_{\alpha_i} & s_{\theta_i} s_{\alpha_i} & a_i c_{\theta_i} \\ s_{\theta_i} & c_{\theta_i} c_{\alpha_i} & -c_{\theta_i} s_{\alpha_i} & a_i s_{\theta_i} \\ 0 & s_{\alpha_i} & c_{\alpha_i} & d_i \\ 0 & 0 & 0 & 1 \end{bmatrix}
\end{aligned}
$$

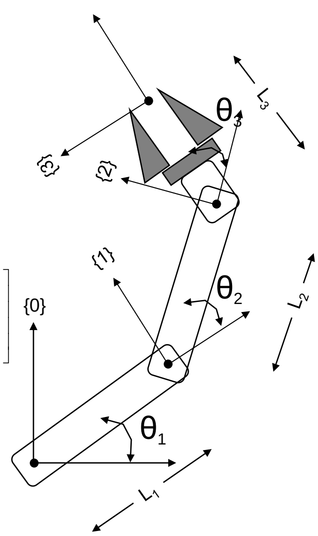
DH Example [1]: RRR Link Manipulator

1. Assign the frames at the joints …
2. Fill DH Table …

Link	a_i	α_i	d_i	θ_i
1	L_1	0	0	θ_1
2	L_2	0	0	θ_2
3	L_3	0	0	θ_3

$$
{}^0A_1 = \begin{bmatrix} c_{\theta_1} & -s_{\theta_1} & 0 & L_1 c_{\theta_1} \\ s_{\theta_1} & c_{\theta_1} & 0 & L_1 s_{\theta_1} \\ 0 & 0 & 1 & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix}
{}^1A_2 = \begin{bmatrix} c_{\theta_2} & -s_{\theta_2} & 0 & L_2 c_{\theta_2} \\ s_{\theta_2} & c_{\theta_2} & 0 & L_2 s_{\theta_2} \\ 0 & 0 & 1 & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix}
{}^2A_3 = \begin{bmatrix} c_{\theta_3} & -s_{\theta_3} & 0 & L_3 c_{\theta_3} \\ s_{\theta_3} & c_{\theta_3} & 0 & L_3 s_{\theta_3} \\ 0 & 0 & 1 & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix}
$$

$$
{}^0T_3 = {}^0A_1 \, {}^1A_2 \, {}^2A_3 = \begin{bmatrix} c_{\theta_{123}} & -s_{\theta_{123}} & 0 & L_1 c_{\theta_1} + L_2 c_{\theta_{12}} + L_3 c_{\theta_{123}} \\ s_{\theta_{123}} & c_{\theta_{123}} & 0 & L_1 s_{\theta_1} + L_2 s_{\theta_{12}} + L_3 s_{\theta_{123}} \\ 0 & 0 & 1 & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix}
$$



DH Example [2]: RRP Link Manipulator

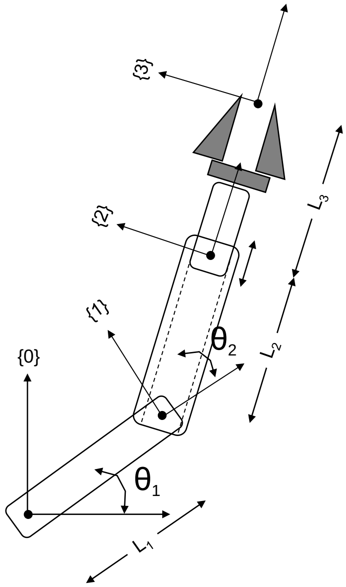
1. Assign the frames at the joints …
2. Fill DH Table …

Link	a_i	α_i	d_i	θ_i
1	L_1	0	0	$\boldsymbol{\theta_1}$
2	L_2	0	0	$\boldsymbol{\theta_2}$
3	$\mathbf{L_3}$	0	0	0

$$
{}^0A_1 = \begin{bmatrix} c_{\theta_1} & -s_{\theta_1} & 0 & L_1 c_{\theta_1} \\ s_{\theta_1} & c_{\theta_1} & 0 & L_1 s_{\theta_1} \\ 0 & 0 & 1 & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix}
{}^1A_2 = \begin{bmatrix} c_{\theta_2} & -s_{\theta_2} & 0 & L_2 c_{\theta_2} \\ s_{\theta_2} & c_{\theta_2} & 0 & L_2 s_{\theta_2} \\ 0 & 0 & 1 & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix}
{}^2A_3 = \begin{bmatrix} 1 & 0 & 0 & L_3 \\ 0 & 1 & 0 & 0 \\ 0 & 0 & 1 & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix}
$$

$$
{}^0T_3 = {}^0A_1\,{}^1A_2\,{}^2A_3
$$

$$
= \begin{bmatrix} c_{\theta_{12}} & -s_{\theta_{12}} & 0 & L_1 c_{\theta_1} + (L_2 + L_3) c_{\theta_{12}} \\ s_{\theta_{12}} & c_{\theta_{12}} & 0 & L_1 s_{\theta_1} + (L_2 + L_3) s_{\theta_{12}} \\ 0 & 0 & 1 & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix}
$$



DH Example [3]: Puma 560

- "Simple" 6R robot exercise for the reader …

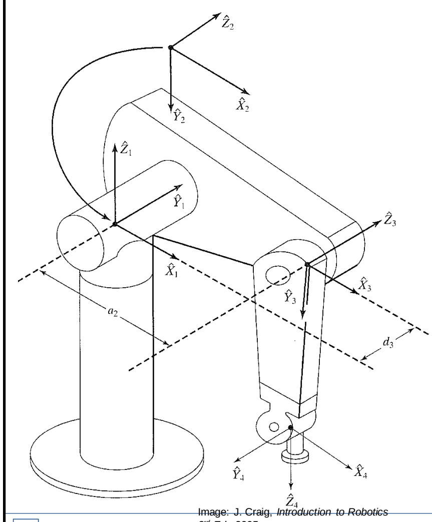
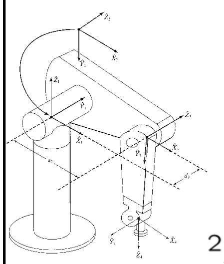


Image: J. Craig, *Introduction to Robotics* 3rd Ed., 2005

Link	a_i	α_i	d_i	θ_i
1	0	0	0	$\boldsymbol{\theta_1}$
2	0	$-\pi/2$	0	$\boldsymbol{\theta_2}$
3	L_2	0	D_3	$\boldsymbol{\theta_3}$
4	L_3	$-\pi/2$	D_4	$\boldsymbol{\theta_4}$
5	0	$\pi/2$	0	$\boldsymbol{\theta_5}$
6	0	$-\pi/2$	0	$\boldsymbol{\theta_6}$

DH Example [3]: Puma 560 [2]



$$
{}^0A_1 = \begin{bmatrix} c_1 & -s_1 & 0 & 0 \\ s_1 & c_1 & 0 & 0 \\ 0 & 0 & 1 & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix} \quad {}^1A_2 = \begin{bmatrix} c_2 & -s_2 & 0 & 0 \\ 0 & 0 & 1 & d_2 \\ -s_2 & -c_2 & 1 & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix}
$$

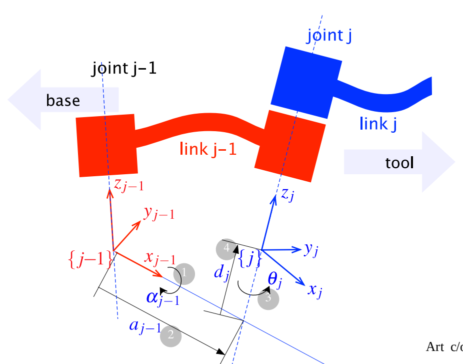
$$
{}^2A_3 = \begin{bmatrix} c_3 & -s_3 & 0 & L_2 \\ s_3 & c_3 & 0 & 0 \\ 0 & 0 & 1 & d_3 \\ 0 & 0 & 0 & 1 \end{bmatrix} \quad {}^3A_4 = \begin{bmatrix} c_4 & -s_4 & 0 & L_3 \\ 0 & 0 & 1 & d_4 \\ -s_4 & -c_4 & 0 & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix}
$$

$$
{}^4A_5 = \begin{bmatrix} c_4 & -s_5 & 0 & L_3 \\ 0 & 0 & 1 & d_4 \\ -s_5 & -c_5 & 0 & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix} \quad {}^5A_6 = \begin{bmatrix} c_6 & -s_6 & 0 & L_3 \\ 0 & 0 & -1 & 0 \\ -s_6 & -c_6 & 0 & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix}
$$

$$
{}^0T_6 = {}^0A_1 {}^1A_2 {}^2A_3 {}^3A_4 {}^4A_5 {}^5A_6
$$

Modified DH

- Made "popular" by Craig's *Intro. to Robotics* book
- Link coordinates attached to the near by joint

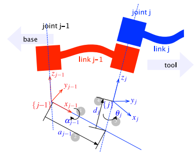


Art c/o P. Corke

- a (trans *x-1*) → α (rot *x-1*) → θ (rot *z*) → d (trans *z*)

Modified DH [2]

- Gives a similar result
  (but it's not commutative)



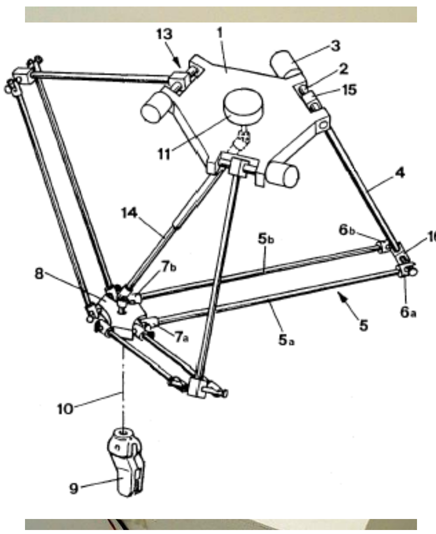
$$\Rightarrow {}^{i-1}A_i = R_x\left(\alpha_{i-1}\right) T_x\left(a_{i-1}\right) R_z\left(\theta_i\right) T_x\left(d_i\right)$$

- Refactoring Standard → to Modified

$$\underbrace{\{R_z(\theta_1)\,T_z(d_1)\,T_x(a_1)\,R_x(\alpha_1)\}}_{\text{DH}_1}\cdot\underbrace{\{R_z(\theta_2)\,T_z(d_2)\,T_x(a_2)\,R_x(\alpha_2)\}}_{\text{DH}_2}\cdot\underbrace{\{R_z(\theta_3)\,T_z(d_3)\}}_{\text{End Effector}}$$

$$=\underbrace{\{R_z(\theta_1)\,T_z(d_1)\}}_{\text{Base}}\cdot\underbrace{\{T_x(a_1)\,R_x(\alpha_1)\,R_z(\theta_2)\,T_z(d_2)\}}_{\text{MDH}_1}\cdot\underbrace{\{T_x(a_2)\,R_x(\alpha_2)\,R_z(\theta_3)\,T_z(d_3)\}}_{\text{MDH}_2}$$

Parallel Manipulators



Sources: Wikipedia, "Delta Robot", ParallelMic.Org, "Delta Parallel Robot", and US Patent 4,976,582

- The "central" Kinematic structure is made up of closed-loop chain(s)
- Compared to Serial Mechanisms:
  - \+ Higher Stiffness
  - \+ Higher Payload
  - \+ Less Inertia
  - – Smaller Workspace
  - – Coordinated Drive System
  - – More Complex & $$$

Symmetrical Parallel Manipulator

A sub-class of Parallel Manipulator:

- # Limbs (***m***) = # DOF (***F***)
- The joints are arranged in an identical pattern
- The # and location of actuated joints are the same

Thus:

- Number of Loops (L): One less than # of limbs

$$L = m - 1 = F - 1$$

- Connectivity (C_k)

$$\sum_{k=1}^{m} C_k = (\lambda + 1)\,F - \lambda$$

Where: λ: The DOF of the space that the system is in (e.g., λ=6 for 3D space).

Cool Robotics Share

http://www.kinemasystems.com/

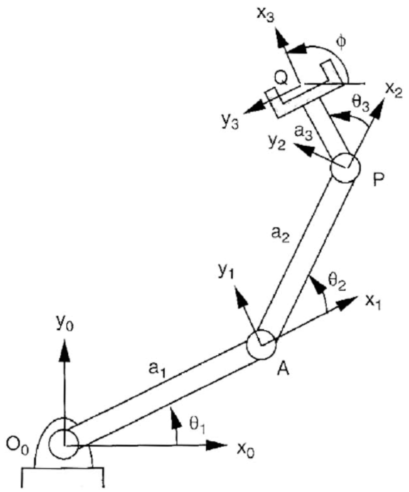
Inverse

Kinematics

Inverse Kinematics [More Generally]

- Freudenstein (1973) referred to the inverse kinematics problem of the most general **6R** manipulator as the “Mount Everest” of kinematic problems.
- Tsai and Morgan (1985) and Primrose (1986) proved that this has at most 16 real solutions.
- Duffy and Crane (1980) derived a closed-form solution for the general **7R** single-loop spatial mechanism.
  - The solution was obtained in the form of a 16 x 16 delerminant in which every element is a second-degree polynomial in one joint variable. The determinant, when expended, should yield a 32nd-degree polynomial equation and hence confirms the upper limit predicted by Roth *et al*. (1973).
- Tsai and Morgan (1985) used the homotopy continuation method to solve the inverse kinematics of the general 6R manipulator and found only 16 solutions
- Raghavan and Roth (1989, 1990) used the dyalitic elimination method to derive a 16th-degree polynomial for the general 6R inverse kinematics problem.

Example: FK/IK of a 3R Planar Arm



- Derived from Tsai (p. 63)

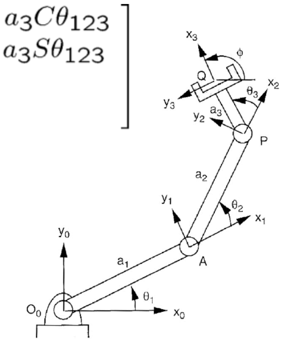
Example: 3R Planar Arm [2]

Position Analysis: 3·Planar 1-R Arm rotating about **Z** **[Ⓩ]**

$${}^0A_3 = {}^0A_1 \cdot {}^1A_2 \cdot {}^2A_3$$

Substituting gives:

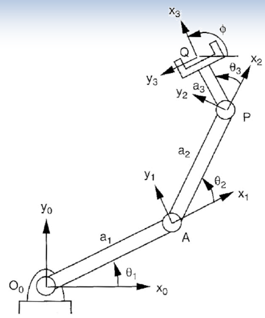
$${}^0A_3 = \begin{bmatrix} C\theta_{123} & -S\theta_{123} & 0 & a_1C\theta_1 + a_2C\theta_{12} + a_3C\theta_{123} \\ S\theta_{123} & C\theta_{123} & 0 & a_1S\theta_1 + a_2S\theta_{12} + a_3S\theta_{123} \\ 0 & 0 & 1 & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix}$$



Example: 3R Planar Arm [2]

Forward Kinematics

(solve for **x given θ** → **x** = *f* (**θ**))



Fairly straight forward:

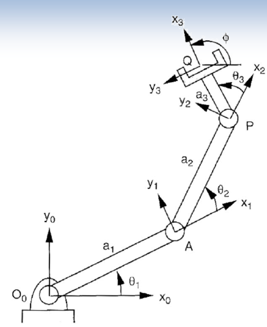
$$^0R_3 = \begin{bmatrix} C\theta_{123} & -S\theta_{123} & 0 \\ S\theta_{123} & C\theta_{123} & 0 \\ 0 & 0 & 1 \end{bmatrix}$$

$$^0P_3 = \begin{bmatrix} a_1C\theta_1 + a_2C\theta_{12} + a_3C\theta_{123} \\ a_1S\theta_1 + a_2S\theta_{12} + a_3S\theta_{123} \\ 0 \end{bmatrix}$$

Example: 3R Planar Arm [3]

Inverse Kinematics

(solve for **θ given x** → **x** = *f* (**θ**))



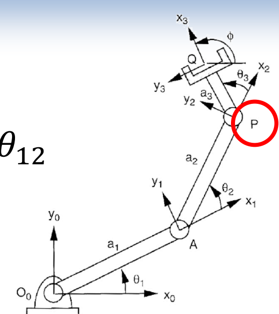
- Start with orientation φ:

$$C\theta_{123} = C\phi,\ S\theta_{123} = S\phi$$
$$\Rightarrow \theta_{123} = \theta_1 + \theta_2 + \theta_3 = \phi$$

- Get overall position $\boldsymbol{q} = [q_x \quad q_y]$:

$$q_x - a_3C\phi = a_1C\theta_1 + a_2C\theta_{12}$$
$$q_y - a_3S\phi = a_1S\theta_1 + a_2S\theta_{12} \ldots$$

Example: 3R Planar Arm [4]



- Introduce $\boldsymbol{p} = [p_x \quad p_y]$ before "wrist"

$$p_x = a_1 C\theta_1 + a_2 C\theta_{12}, p_y = a_1 S\theta_1 + a_2 S\theta_{12}$$
$$\Rightarrow p_x^2 + p_y^2 = a_1^2 + a_2^2 + 2a_1 a_2 C\theta_2$$

- Solve for θ_2:

$$\theta_2 = \cos^{-1}\kappa, \kappa = \frac{p_x^2+p_y^2-a_1^2-a_2^2}{2a_1a_2} \quad (2\ \mathbb{R} \text{ roots if } |\kappa|<1)$$

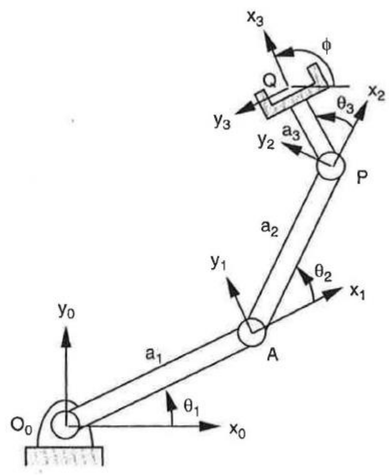
- Solve for θ_1:

$$C\theta_1 = \frac{p_x(a_1+a_2C\theta_2)+p_y a_2 S\theta_2}{a_1^2+a_2^2+2a_1a_2C\theta_2}, S\theta_1 = \frac{-p_x a_2 S\theta_2+p_y(a_1+a_2C\theta_2)}{a_1^2+a_2^2+2a_1a_2C\theta_2}$$

$$\theta_1 = atan2(S\theta_1, C\theta_1)$$

Inverse Kinematics: Example I

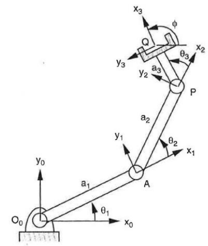
Planar Manipulator:



Inverse Kinematics: Example I

- Forward Kinematics:

[For the Frame {Q} at the end effector]:



$$\begin{bmatrix} q_x \\ q_y \\ q_z \\ 1 \end{bmatrix} = {}^0A_3 \begin{bmatrix} 0 \\ 0 \\ 0 \\ 1 \end{bmatrix} = \begin{bmatrix} a_1 c\theta_1 + a_2 c\theta_{12} + a_3 c\theta_{123} \\ a_1 s\theta_1 + a_2 s\theta_{12} + a_3 s\theta_{123} \\ 0 \\ 1 \end{bmatrix}$$

$\because$

$${}^0A_3 = \begin{bmatrix} c\theta_{123} & -s\theta_{123} & 0 & a_1 c\theta_1 + a_2 c\theta_{12} + a_3 c\theta_{123} \\ s\theta_{123} & c\theta_{123} & 0 & a_1 s\theta_1 + a_2 s\theta_{12} + a_3 s\theta_{123} \\ 0 & 0 & 1 & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix}$$

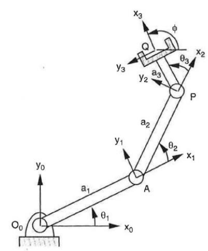
- For an arbitrary point **G** in the end effector: ${}^3\mathbf{g} = [g_u, g_v, 0, 1]^T$

$$\begin{bmatrix} g_x \\ g_y \\ g_z \\ 1 \end{bmatrix} = {}^0A_3 \begin{bmatrix} g_u \\ g_v \\ 0 \\ 1 \end{bmatrix} = \begin{bmatrix} g_u c\theta_{123} - g_v s\theta_{123} + a_1 c\theta_1 + a_2 c\theta_{12} + a_3 c\theta_{123} \\ g_u s\theta_{123} + g_v c\theta_{123} + a_1 s\theta_1 + a_2 s\theta_{12} + a_3 s\theta_{123} \\ 0 \\ 1 \end{bmatrix}$$

Inverse Kinematics: Example I

- Forward Kinematics:

[For the Frame {Q} at the end effector]:



$$\begin{bmatrix} q_x \\ q_y \\ q_z \\ 1 \end{bmatrix} = {}^0A_3 \begin{bmatrix} 0 \\ 0 \\ 0 \\ 1 \end{bmatrix} = \begin{bmatrix} a_1 c\theta_1 + a_2 c\theta_{12} + a_3 c\theta_{123} \\ a_1 s\theta_1 + a_2 s\theta_{12} + a_3 s\theta_{123} \\ 0 \\ 1 \end{bmatrix}$$

$\because$

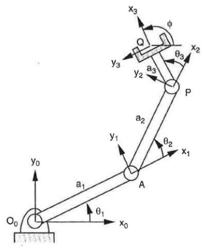
$${}^0A_3 = \begin{bmatrix} c\theta_{123} & -s\theta_{123} & 0 & a_1 c\theta_1 + a_2 c\theta_{12} + a_3 c\theta_{123} \\ s\theta_{123} & c\theta_{123} & 0 & a_1 s\theta_1 + a_2 s\theta_{12} + a_3 s\theta_{123} \\ 0 & 0 & 1 & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix}$$

- For an arbitrary point **G** in the end effector: ${}^3\mathbf{g} = [g_u, g_v, 0, 1]^T$

$$\begin{bmatrix} g_x \\ g_y \\ g_z \\ 1 \end{bmatrix} = {}^0A_3 \begin{bmatrix} g_u \\ g_v \\ 0 \\ 1 \end{bmatrix} = \begin{bmatrix} g_u c\theta_{123} - g_v s\theta_{123} + a_1 c\theta_1 + a_2 c\theta_{12} + a_3 c\theta_{123} \\ g_u s\theta_{123} + g_v c\theta_{123} + a_1 s\theta_1 + a_2 s\theta_{12} + a_3 s\theta_{123} \\ 0 \\ 1 \end{bmatrix}$$

Inverse Kinematics: Example I

- Inverse Kinematics:
  - Set the final position equal to the Forward Transformation Matrix $^{0}\mathbf{A}_3$:



$$^{0}A_3 = \begin{bmatrix} c\phi & -s\phi & 0 & q_x \\ s\phi & c\phi & 0 & q_y \\ 0 & 0 & 1 & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix}$$

- The solution strategy is to equate the elements of $^{0}\mathbf{A}_3$ to that of the given position (q_x, q_y) and orientation ϕ

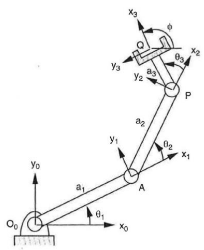
Inverse Kinematics: Example I

- Orientation (ϕ):

$$c\theta_{123} = c\phi,$$

$$s\theta_{123} = s\phi.$$

$$\theta_{123} = \theta_1 + \theta_2 + \theta_3 = \phi.$$



- Now Position of the 2DOF point **P**:

$$p_x = a_1 c\theta_1 + a_2 c\theta_{12},$$

$$p_y = a_1 s\theta_1 + a_2 s\theta_{12},$$

$$\therefore \quad p_x = q_x - a_3 c\phi \qquad p_y = q_y - a_3 s\phi$$

- Substitute: θ_3 disappears and now we can eliminate θ_1:

$$p_x^2 + p_y^2 = a_1^2 + a_2^2 + 2a_1 a_2 c\theta_2.$$

Inverse Kinematics: Example I

- we can eliminate θ_1…

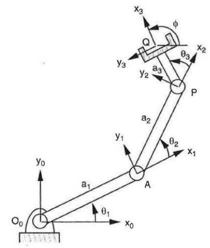
  $p_x^2 + p_y^2 = a_1^2 + a_2^2 + 2a_1a_2c\theta_2.$

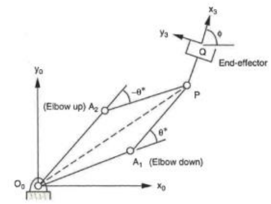
- Then solve for θ_{12}:

  $\theta_2 = \cos^{-1}\kappa, \qquad \kappa = \dfrac{p_x^2 + p_y^2 - a_1^2 - a_2^2}{2a_1a_2}$

  - This gives 2 real ($\mathbb{R}$) roots if $|\kappa| < 1$
  - One double root if $|\kappa| = 1$
  - No real roots if $|\kappa| > 1$

- Elbow up/down:
  - In general, **if** θ_2 is a solution **then** $-\theta_2$ is a solution





Inverse Kinematics: Example I

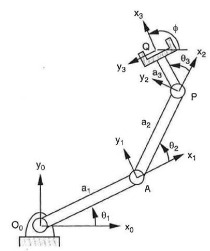
- Solving for θ_1…
  - Corresponding to each θ_2, we can solve θ_1

$$(a_1 + a_2c\theta_2)c\theta_1 - (a_2s\theta_2)s\theta_1 = p_x$$
$$(a_2s\theta_2)c\theta_1 + (a_1 + a_2c\theta_2)s\theta_1 = p_y$$

$$c\theta_1 = \frac{p_x(a_1 + a_2c\theta_2) + p_y a_2 s\theta_2}{\Delta},$$
$$s\theta_1 = \frac{-p_x a_2 s\theta_2 + p_y(a_1 + a_2c\theta_2)}{\Delta}$$

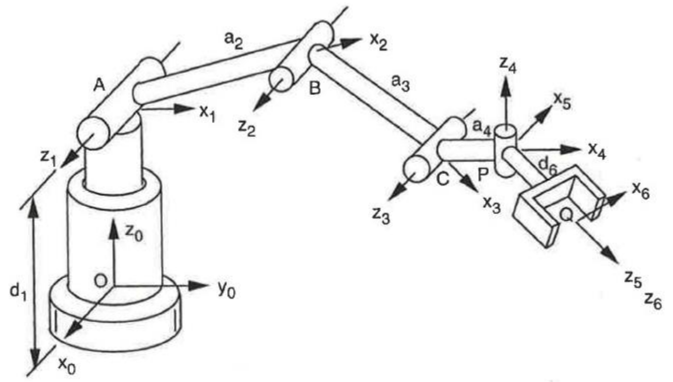
$$\Delta = a_1^2 + a_2^2 + 2a_1a_2c\theta_2$$

$$\boxed{\theta_1 = \mathrm{Atan2}(s\theta_1, c\theta_1).}$$



Inverse Kinematics: Example II

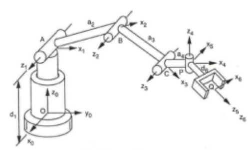
Elbow Manipulator:



Inverse Kinematics: Example II

- Target Position:

$\mathbf{u} = [u_x, u_y, u_z]^{\mathrm{T}}, \quad \mathbf{v} = [v_x, v_y, v_z]^{\mathrm{T}}, \quad \mathbf{w} = [w_x, w_y, w_z]^{\mathrm{T}}$, and
$\mathbf{p} = [p_x, p_y, p_z]^{\mathrm{T}}$.



- Transformation Matrices:

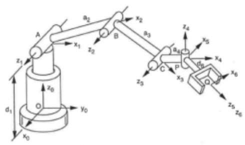
$$A_1 = \begin{bmatrix} c\theta_1 & -s\theta_1 & 0 & 0 \\ s\theta_1 & c\theta_1 & 0 & 0 \\ 0 & 0 & 1 & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix}, \quad ({}^0A_1)^{-1} = \begin{bmatrix} c\theta_1 & s\theta_1 & 0 & 0 \\ -s\theta_1 & c\theta_1 & 0 & 0 \\ 0 & 0 & 1 & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix}$$

$$A_2 = \begin{bmatrix} c\theta_2 & 0 & -s\theta_2 & 0 \\ 0 & 1 & 0 & 0 \\ s\theta_2 & 0 & c\theta_2 & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix},$$

$$A_3 = \begin{bmatrix} c\theta_3 & 0 & -s\theta_3 & a_2(1 - c\theta_3) \\ 0 & 1 & 0 & 0 \\ s\theta_3 & 0 & c\theta_3 & -a_2 s\theta_3 \\ 0 & 0 & 0 & 1 \end{bmatrix} \quad A_4 = \begin{bmatrix} c\theta_4 & 0 & -s\theta_4 & (a_2 + a_3)(1 - c\theta_4) \\ 0 & 1 & 0 & 0 \\ s\theta_4 & 0 & c\theta_4 & -(a_2 + a_3)s\theta_4 \\ 0 & 0 & 0 & 1 \end{bmatrix} \quad A_5 = \begin{bmatrix} c\theta_5 & -s\theta_5 & 0 & (a_2 + a_3 + a_4)(1 - c\theta_5) \\ s\theta_5 & c\theta_5 & 0 & -(a_2 + a_3 + a_4)s\theta_5 \\ 0 & 0 & 1 & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix}$$

Inverse Kinematics: Example II

- Key Matrix Products:

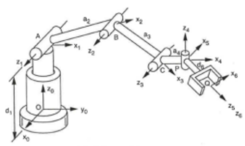


$$A_2A_3A_4 = \begin{bmatrix} c\theta_{234} & 0 & -s\theta_{234} & a_2c\theta_2 + a_3c\theta_{23} - (a_2+a_3)c\theta_{234} \\ 0 & 1 & 0 & 0 \\ s\theta_{234} & 0 & c\theta_{234} & a_2s\theta_2 + a_3s\theta_{23} - (a_2+a_3)s\theta_{234} \\ 0 & 0 & 0 & 1 \end{bmatrix}$$

$$A_1A_2A_3A_4 = \begin{bmatrix} c\theta_1c\theta_{234} & -s\theta_1 & -c\theta_1s\theta_{234} & c\theta_1[a_2c\theta_2 + a_3c\theta_{23} - (a_2+a_3)c\theta_{234}] \\ s\theta_1c\theta_{234} & c\theta_1 & -s\theta_1s\theta_{234} & s\theta_1[a_2c\theta_2 + a_3c\theta_{23} - (a_2+a_3)c\theta_{234}] \\ s\theta_{234} & 0 & c\theta_{234} & [a_2s\theta_2 + a_3s\theta_{23} - (a_2+a_3)s\theta_{234}] \\ 0 & 0 & 0 & 1 \end{bmatrix}$$

Inverse Kinematics: Example II

- Inverse Kinematics:



$$\mathbf{p} = A_1A_2A_3A_4\mathbf{p}_0.$$

$$A_1^{-1}\begin{bmatrix} p_x \\ p_y \\ p_z \\ 1 \end{bmatrix} = A_2A_3A_4\begin{bmatrix} a_2+a_3+a_4 \\ 0 \\ 0 \\ 1 \end{bmatrix}$$

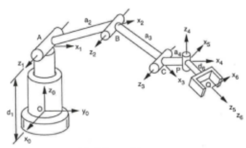
$$p_xc\theta_1 + p_ys\theta_1 = a_2c\theta_2 + a_3c\theta_{23} + a_4c\theta_{234},$$

$$-p_xs\theta_1 + p_yc\theta_1 = 0,$$

$$p_z = a_2s\theta_2 + a_3s\theta_{23} + a_4s\theta_{234}.$$

Inverse Kinematics: Example II

- Solving the System:



$$\theta_1 = \tan^{-1}\frac{p_y}{p_x}.$$

$$\theta_5 = \sin^{-1}(-w_x s\theta_1 + w_y c\theta_1).$$

$$\theta_{234} = \text{Atan2}\left[w_z/c\theta_5,\ (w_x c\theta_1 + w_y s\theta_1)/c\theta_5\right].$$

$$a_2 c\theta_2 + a_3 c\theta_{23} = k_1, \qquad k_1 = p_x c\theta_1 + p_y s\theta_1 - a_4 c\theta_{234}$$

$$a_2 s\theta_2 + a_3 s\theta_{23} = k_2, \qquad k_2 = p_z - a_4 s\theta_{234}$$

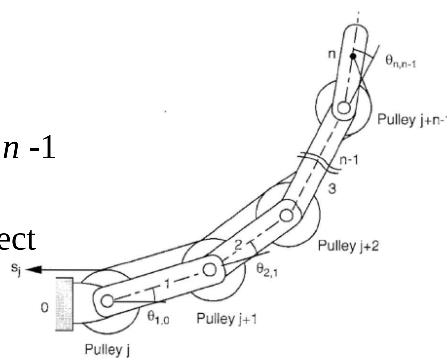
$$a_2^2 + a_3^2 + 2a_2 a_3 c\theta_3 = k_1^2 + k_2^2.$$

$$\theta_3 = \cos^{-1}\frac{k_1^2 + k_2^2 - a_2^2 - a_3^2}{2a_2 a_3}.$$

$$\theta_6 = \text{Atan2}(s\theta_6, c\theta_6).$$

Advanced Concept: Tendon-Driven Manipulators

- Tendons may be modelled as a transmission line
- in which the links are labeled sequentially from 0 to n and the pulleys are labeled from *j* to *j* + *n* -1
- Let θ_{ji} denote the angular displacement of link *j* with respect to link *i.*
- We can write a circuit equation once for each pulley pair as follows:



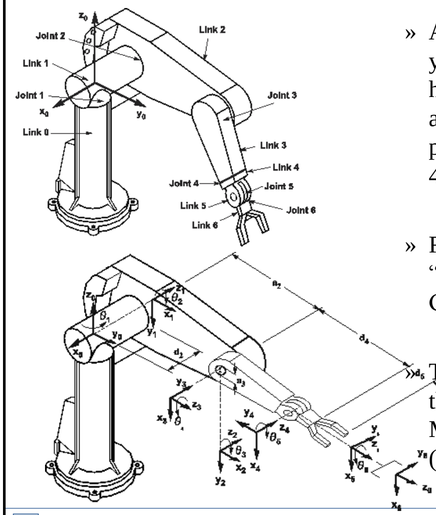
$$r_{j+i-1}\theta_{j+i-1,i} = \pm r_{j+i}\theta_{j+i,i} \qquad \text{for } i = 1, 2, \ldots, n-1.$$

$$\theta_{j+i-1,i} = \theta_{j+i-1,i-1} - \theta_{i,i-1} \qquad \text{for } i = 1, 2, \ldots, n.$$

$$\theta_{j,0} = \theta_{1,0} \pm (r_{j+1}/r_j)\theta_{2,1} \pm \cdots \pm (r_{j+n-1}/r_j)\theta_{n,n-1}.$$

Inverse Kinematics

- What about a more complicated mechanism?



» A sufficient condition for a serial manipulator to yield a closed-form inverse kinematics solution is to have any three consecutive joint axes intersecting at a common point or any three consecutive joint axes parallel to each other. (Pieper and Roth (1969) via 4×4 matrix method)

» Raghavan and Roth 1990
"Kinematic Analysis of the 6R Manipulator of General Geometry"

» Tsai and Morgan 1985, "Solving the Kinematics of the Most General Six and Five-Dcgree-of-Freedom Manipulators by Continuation Methods" (posted online)

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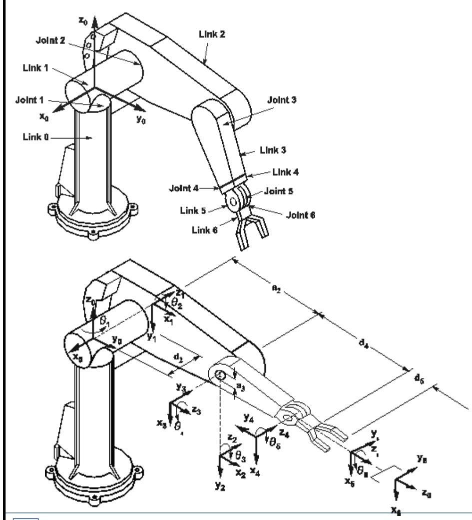


$$ {}^{0}\boldsymbol{T}_6 = {}^{0}\boldsymbol{T}_1\, {}^{1}\boldsymbol{T}_2\, {}^{2}\boldsymbol{T}_3\, {}^{3}\boldsymbol{T}_4\, {}^{4}\boldsymbol{T}_5\, {}^{5}\boldsymbol{T}_6 = \begin{pmatrix} n_x & s_x & a_x & p_x \\ n_y & s_y & a_y & p_y \\ n_z & s_z & a_z & p_z \\ 0 & 0 & 0 & 1 \end{pmatrix} $$

$$ \begin{aligned} n_x &= c_1(c_{23}(c_4c_5c_6 - s_4s_6) - s_{23}s_5c_6) - s_1(s_4c_5c_6 + c_4s_6) \\ n_y &= s_1(c_{23}(c_4c_5c_6 - s_4s_6) - s_{23}s_5c_6) + c_1(s_4c_5c_6 + c_4s_6) \\ n_z &= -s_{23}(c_4c_5c_6 - s_4s_6) - c_{23}s_5c_6 \\ s_x &= c_1(-c_{23}(c_4c_5s_6 + s_4c_6) + s_{23}s_5s_6) - s_1(-s_4c_5s_6 + c_4c_6) \\ s_y &= s_1(-c_{23}(c_4c_5s_6 + s_4c_6) + s_{23}s_5s_6) + c_1(-s_4c_5s_6 + c_4c_6) \\ s_z &= s_{23}(c_4c_5s_6 + s_4c_6) - c_{23}s_5s_6 \\ a_x &= c_1(c_{23}c_4s_5 + s_{23}c_5) - s_1s_4s_5 \\ a_y &= s_1(c_{23}c_4s_5 + s_{23}c_5) + c_1s_4s_5 \\ a_z &= -s_{23}c_4s_5 + c_{23}c_5) \\ p_x &= c_1(d_6(c_{23}c_4s_5 + s_{23}c_5) + s_{23}d_4 + a_3c_{23} + a_2c_2) - s_1(d_6s_4s_5 + d_2) \\ p_y &= s_1(d_6(c_{23}c_4s_5 + s_{23}c_5) + s_{23}d_4 + a_3c_{23} + a_2c_2) + c_1(d_6s_4s_5 + d_2) \\ p_z &= d_6(c_{23}c_5 - s_{23}c_4s_5) + c_{23}d_4 - a_3s_{23} - a_2s_2 \end{aligned} $$

Symmetrical Parallel Manipulator

A sub-class of Parallel Manipulator:

- # Limbs (***m***) = # DOF (***F***)
- The joints are arranged in an identical pattern
- The # and location of actuated joints are the same

Thus:

- Number of Loops (L): One less than # of limbs

$$L = m - 1 = F - 1$$

- Connectivity (C_k)

$$\sum_{k=1}^{m} C_k = (\lambda + 1)\,F - \lambda$$

Where: λ: The DOF of the space that the system is in (e.g., λ=6 for 3D space).

Robot Dynamics

Robot Dynamics

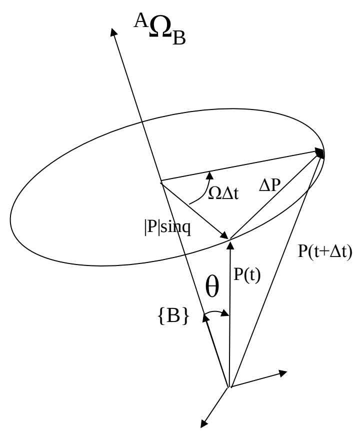
Angular Velocity

- If we look at a small timeslice as a frame rotates with a moving point, we find

$$|\Delta \mathbf{P}| = \left(\left|{}^{A}\mathbf{P}\right| \sin\theta\right)\left(\left|{}^{A}\Omega_B\right| \Delta t\right)$$

$$\frac{|\Delta \mathbf{P}|}{\Delta t} = \left(\left|{}^{A}\mathbf{P}\right| \sin\theta\right)\left(\left|{}^{A}\Omega_B\right|\right)$$

$$= {}^{A}\Omega_B \times {}^{A}\mathbf{P}$$



$${}^{A}\mathbf{V}_P = {}^{A}\Omega_B \times {}^{A}R_B {}^{B}\mathbf{P}$$

Velocity

- Recall that we can specify a point in one frame relative to another as

$$^{A}\mathbf{P} = {}^{A}\mathbf{P}_{B} + {}^{A}_{B}\mathbf{R}\,{}^{B}\mathbf{P}$$

- Differentiating w/r/t to **t** we find

$$^{A}\mathbf{V}_{P} = \frac{d}{dt}{}^{A}\mathbf{P} = \lim_{\Delta t \to 0} \frac{^{A}\mathbf{P}(t+\Delta t) - {}^{A}\mathbf{P}(t)}{\Delta t}$$
$$= {}^{A}\dot{\mathbf{P}}_{B} + {}^{A}_{B}\mathbf{R}\,{}^{B}\dot{\mathbf{P}} + {}^{A}_{B}\dot{\mathbf{R}}\,{}^{B}\mathbf{P}$$

- This can be rewritten as

$$^{A}\mathbf{V}_{P} = {}^{A}\mathbf{V}_{BORG} + {}^{A}\mathbf{R}_{B}\,{}^{B}\mathbf{V}_{P} + {}^{A}\Omega_{B} \times {}^{A}\mathbf{R}_{B}\,{}^{B}\mathbf{P}$$

Skew – Symmetric Matrix

$$\mathbf{V} = \omega \times \mathbf{r}$$

$$\Omega = \begin{bmatrix} 0 & -\omega_z & \omega_y \\ \omega_z & 0 & -\omega_x \\ -\omega_y & \omega_x & 0 \end{bmatrix}$$

$$\rightarrow \mathbf{V} = \Omega\mathbf{r}$$

Velocity Representations

- Euler Angles
  - For Z-Y-X (α,β,γ):

$$\begin{pmatrix} \dot{\alpha} \\ \dot{\beta} \\ \dot{\gamma} \end{pmatrix} = \begin{pmatrix} -S\beta & 0 & 1 \\ C\beta S\gamma & C\gamma & 0 \\ C\beta C\gamma & -S\beta & 0 \end{pmatrix} \begin{pmatrix} \omega_x \\ \omega_y \\ \omega_z \end{pmatrix}$$

- Quaternions

$$\begin{pmatrix} \dot{\varepsilon}_0 \\ \dot{\varepsilon}_1 \\ \dot{\varepsilon}_2 \\ \dot{\varepsilon}_3 \end{pmatrix} = \frac{1}{2} \begin{pmatrix} \varepsilon_1 & -\varepsilon_2 & -\varepsilon_3 \\ \varepsilon_0 & \varepsilon_3 & -\varepsilon_2 \\ -\varepsilon_3 & \varepsilon_0 & \varepsilon_1 \\ \varepsilon_2 & -\varepsilon_1 & \varepsilon_0 \end{pmatrix} \begin{pmatrix} \omega_x \\ \omega_y \\ \omega_z \end{pmatrix}$$

Manipulator Velocities

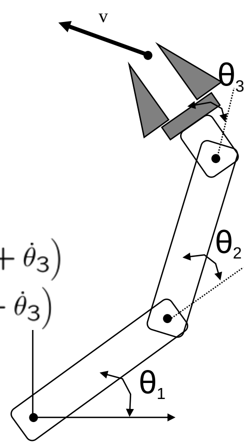
- Consider again the schematic of the planar manipulator shown. We found that the end effector position is given by

$$x = L_1 \cos\theta_1 + L_2 \cos(\theta_1+\theta_2) + L_3 \cos(\theta_1+\theta_2+\theta_3)$$
$$y = L_1 \sin\theta_1 + L_2 \sin(\theta_1+\theta_2) + L_3 \sin(\theta_1+\theta_2+\theta_3)$$

- Differentiating w/r/t to t

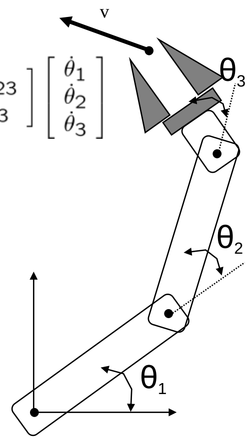
$$\dot{x} = -L_1 s_1 \dot{\theta}_1 - L_2 s_{12}\left(\dot{\theta}_1+\dot{\theta}_2\right) - L_3 s_{123}\left(\dot{\theta}_1+\dot{\theta}_2+\dot{\theta}_3\right)$$
$$\dot{y} = L_1 c_1 \dot{\theta}_1 + L_2 c_{12}\left(\dot{\theta}_1+\dot{\theta}_2\right) + L_3 c_{123}\left(\dot{\theta}_1+\dot{\theta}_2+\dot{\theta}_3\right)$$

- This gives the end effector velocity as a function of pose and joint velocities



Manipulator Velocities [2]

- Rearranging, we can recast this relation in matrix form



$$\begin{bmatrix} \dot{x} \\ \dot{y} \end{bmatrix} = \begin{bmatrix} -L_1\,\mathrm{s}_1 - L_2\,\mathrm{s}_{12} - L_3\,\mathrm{s}_{123} & -L_2\,\mathrm{s}_{12} - L_3\,\mathrm{s}_{123} & -L_3\,\mathrm{s}_{123} \\ L_1\,\mathrm{c}_1 + L_2\,\mathrm{c}_{12} + L_3\,\mathrm{c}_{123} & L_2\,\mathrm{c}_{12} + L_3\,\mathrm{c}_{123} & L_3\,\mathrm{c}_{123} \end{bmatrix} \begin{bmatrix} \dot{\theta}_1 \\ \dot{\theta}_2 \\ \dot{\theta}_3 \end{bmatrix}$$

- Or

$$\begin{bmatrix} \dot{x} \\ \dot{y} \end{bmatrix} = \begin{bmatrix} \frac{\partial x}{\partial \theta_1} & \frac{\partial x}{\partial \theta_2} & \frac{\partial x}{\partial \theta_3} \\ \frac{\partial y}{\partial \theta_1} & \frac{\partial y}{\partial \theta_2} & \frac{\partial y}{\partial \theta_3} \end{bmatrix} \begin{bmatrix} \dot{\theta}_1 \\ \dot{\theta}_2 \\ \dot{\theta}_3 \end{bmatrix}$$

- The resulting matrix is called the Jacobian and provides us with a mapping from Joint Space to Cartesian Space.

Moving On…Differential Motion

- Transformations also encode differential relationships
- Consider a manipulator (say 2DOF, RR)

$$x(\theta_1, \theta_2) = l_1 \cos(\theta_1) + l_2 \cos(\theta_1 + \theta_2)$$
$$y(\theta_1, \theta_2) = l_1 \sin(\theta_1) + l_2 \sin(\theta_1 + \theta_2)$$

- Differentiating with respect to the **angles** gives:

$$dx = \frac{\partial x(\theta_1, \theta_2)}{\partial \theta_1} d\theta_1 + \frac{\partial x(\theta_1, \theta_2)}{\partial \theta_2} d\theta_2$$

$$dy = \frac{\partial y(\theta_1, \theta_2)}{\partial \theta_1} d\theta_1 + \frac{\partial y(\theta_1, \theta_2)}{\partial \theta_2} d\theta_2$$

Differential Motion [2]

- Viewing this as a matrix → Jacobian

$$d\mathbf{x} = J d\theta$$

$$J = \begin{bmatrix} -l_1 \sin(\theta_1) - l_2 \sin(\theta_1 + \theta_2) & -l_2 \sin(\theta_1 + \theta_2) \\ l_1 \cos(\theta_1) + l_2 \cos(\theta_1 + \theta_2) & l_2 \cos(\theta_1 + \theta_2) \end{bmatrix}$$

$$J = \begin{bmatrix} [J_1] & [J_2] \end{bmatrix}$$

$$v = J_1 \dot{\theta}_1 + J_2 \dot{\theta}_2$$

Infinitesimal Rotations

- $\cos(d\phi) = 1, \sin(d\phi) = d\phi$

$$\mathbf{R}_x(d\phi) = \begin{bmatrix} 1 & 0 & 0 \\ 0 & cd\phi & -sd\phi \\ 0 & sd\phi & cd\phi \end{bmatrix} \approx \begin{bmatrix} 1 & 0 & 0 \\ 0 & 1 & -d\phi_x \\ 0 & d\phi_x & 1 \end{bmatrix}$$

$$\mathbf{R}_y(d\phi) = \begin{bmatrix} cd\phi & 0 & sd\phi \\ 0 & 1 & 0 \\ -sd\phi & 0 & cd\phi \end{bmatrix} \approx \begin{bmatrix} 1 & 0 & d\phi_y \\ 0 & 1 & 0 \\ -d\phi_y & 0 & 1 \end{bmatrix}$$

$$\mathbf{R}_z(d\phi) = \begin{bmatrix} cd\phi & -sd\phi & 0 \\ sd\phi & cd\phi & 0 \\ 0 & 0 & 1 \end{bmatrix} \approx \begin{bmatrix} 1 & -d\phi_z & 0 \\ d\phi_z & 1 & 0 \\ 0 & 0 & 1 \end{bmatrix}$$

- Note that:

$$R_x(d\varphi) R_y(d\varphi) = R_y(d\varphi) R_x(d\varphi)$$

→ Therefore … they **commute**

Summary

- Many ways to view a rotation
  - Rotation matrix
  - Euler angles
  - Quaternions
  - Direction Cosines
  - Screw Vectors

- Homogenous transformations
  - Based on homogeneous coordinates