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Robotics: Differential Kinematics and Statics

Vladimír Petrík

vladimir.petrik@cvut.cz

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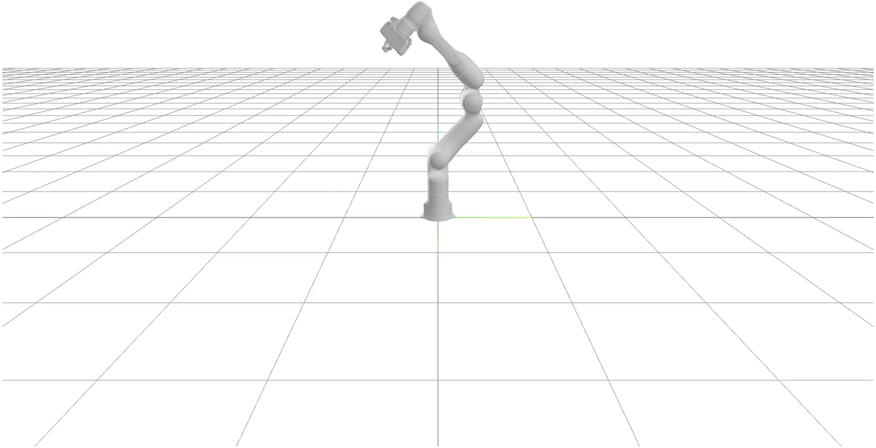
Motivation



Differential kinematics

- We know how to compute end-effector pose from the configuration
  - forward kinematics
  - $\boldsymbol{x}(t) = f_{\mathsf{fk}}(\boldsymbol{q}(t))$
  - $\boldsymbol{x}(t)$ is expressed in task-space, *i.e.* $SE(2)$, $SE(3)$, or $\mathbb{R}^2$, $\mathbb{R}^3$ for position only
  - $\boldsymbol{q}(t) \in \mathbb{R}^N$ is configuration (joint space)
  - t represents time

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  - t represents time
- Differential kinematics
  - relates end-effector velocity to joint velocities
  - $\dot{\boldsymbol{x}} = \frac{\mathrm{d}\boldsymbol{x}(t)}{\mathrm{d}t} \in \mathbb{R}^M$
  - Jacobian of the manipulator is core structure in the analysis

Jacobian

Forward kinematics:

$$\boldsymbol{x}(t) = f_{\mathsf{fk}}(\boldsymbol{q}(t))$$

Jacobian:

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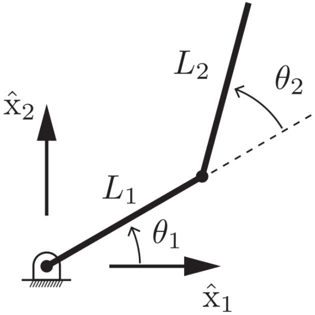
$$\begin{aligned}
\dot{\boldsymbol{x}} &= \frac{\mathrm{d}\boldsymbol{x}(t)}{\mathrm{d}t} \\
&= \frac{\partial f_{\mathsf{fk}}(\boldsymbol{q})}{\partial \boldsymbol{q}} \frac{\mathrm{d}\boldsymbol{q}(t)}{\mathrm{d}t} \\
&= \frac{\partial f_{\mathsf{fk}}(\boldsymbol{q})}{\partial \boldsymbol{q}} \dot{\boldsymbol{q}} \\
&= J(\boldsymbol{q})\dot{\boldsymbol{q}}
\end{aligned}$$

$$J(\boldsymbol{q}) = \frac{\partial f_{\mathsf{fk}}(\boldsymbol{q})}{\partial \boldsymbol{q}} \in \mathbb{R}^{M \times N}$$

Planar robot example



- FK: $\boldsymbol{q} = (\theta_1, \theta_2)^\top \to (x, y)^\top$

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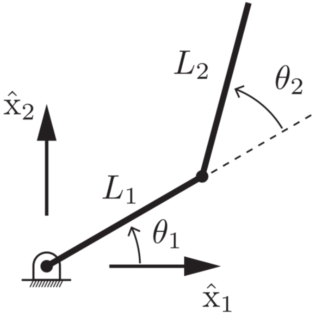

- FK: $\boldsymbol{q} = (\theta_1, \theta_2)^\top \rightarrow (x, y)^\top$
  - $x = L_1 \cos\theta_1 + L_2 \cos(\theta_1 + \theta_2)$
  - $y = L_1 \sin\theta_1 + L_2 \sin(\theta_1 + \theta_2)$
- $\dot{\boldsymbol{x}} = ?$

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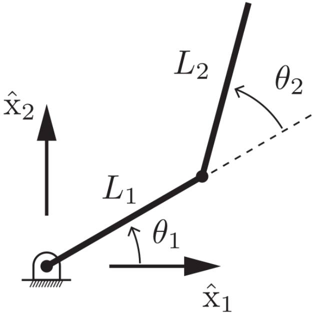

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- $\dot{\boldsymbol{x}} = ?$
  - $\dot{x}_1 = -L_1\dot{\theta}_1 \sin\theta_1 - L_2(\dot{\theta}_1 + \dot{\theta}_2)\sin(\theta_1 + \theta_2)$
  - $\dot{y}_1 = L_1\dot{\theta}_1 \cos\theta_1 + L_2(\dot{\theta}_1 + \dot{\theta}_2)\cos(\theta_1 + \theta_2)$

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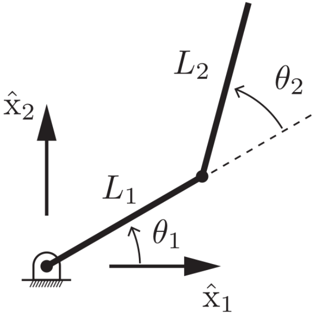

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  - $\dot{y}_1 = L_1\dot{\theta}_1 \cos\theta_1 + L_2(\dot{\theta}_1 + \dot{\theta}_2)\cos(\theta_1 + \theta_2)$
  - $J(\boldsymbol{q}) = \begin{pmatrix} -L_1 \sin\theta_1 - L_2 \sin(\theta_1 + \theta_2) & -L_2 \sin(\theta_1 + \theta_2) \\ L_1 \cos\theta_1 + L_2 \cos(\theta_1 + \theta_2) & L_2 \cos(\theta_1 + \theta_2) \end{pmatrix}$
  - Jacobian depends on the configuration $\boldsymbol{q}$

Jacobian dimension

- $J(\boldsymbol{q}) = \frac{\partial f_{\mathsf{fk}}(\boldsymbol{q})}{\partial \boldsymbol{q}} \in \mathbb{R}^{M \times N}$
- M task-space DoF
- N joint-space DoF

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- Redundant robots: $N > M$
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- 2 DoF robot with translation task space: 2×2
- 2 DoF robot with $SE(2)$ task space: 3×2
- 5 DoF robot with $SE(2)$ task space:

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- 5 DoF robot with $SE(2)$ task space: 3×5
- 6 DoF robot with $SE(3)$ task space:

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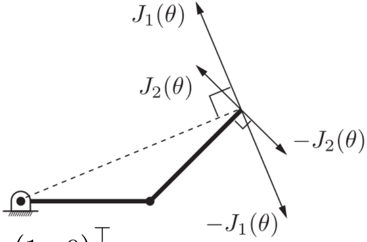
- 2 DoF robot with $SE(2)$ task space: 3×2
- 5 DoF robot with $SE(2)$ task space: 3×5
- 6 DoF robot with $SE(3)$ task space: 6×6
- 7 DoF robot with $SE(3)$ task space: 6×7

Jacobian properties



- $J(\boldsymbol{q}) = \begin{pmatrix} J_1(\boldsymbol{q}) & J_2(\boldsymbol{q}) \end{pmatrix}$
- First column corresponds to the end-point velocity for $\dot{\boldsymbol{q}} = \begin{pmatrix} 1 & 0 \end{pmatrix}^\top$
- Second column corresponds to the end-point velocity for $\dot{\boldsymbol{q}} = \begin{pmatrix} 0 & 1 \end{pmatrix}^\top$
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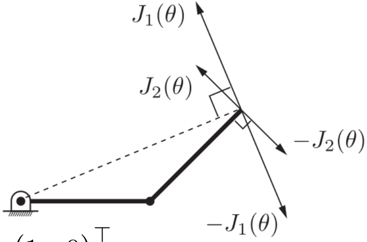

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  - when they are collinear?

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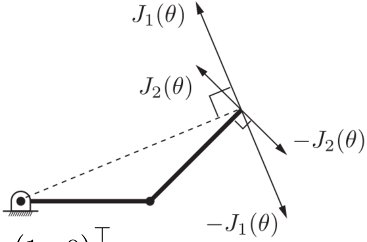

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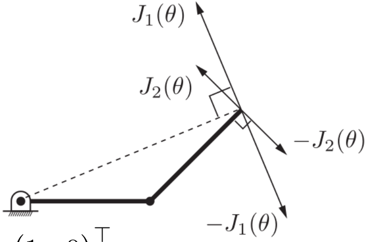

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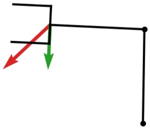
  - when they are collinear? *e.g.* $\theta_2 = 0$
  - Jacobian is singular matrix $\rightarrow$ configurations are called **singularities**
  - rank of Jacobian is not maximal
  - end-effector is unable to generate velocity in a certain direction

Jacobian columns visualization



How to compute jacobian numerically

- Finite difference method
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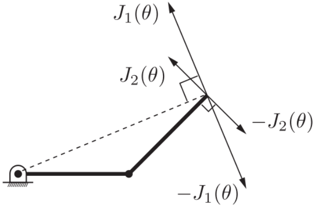
- Repeat for every element of J
- Slow to compute, easy to implement $\rightarrow$ used in testing

How to compute jacobian analytically



- $J = \begin{pmatrix} J_v & J_w \end{pmatrix}^\top$ *i.e.* translation and rotation part
- Translation part:
  - i-th column $(\boldsymbol{n}_S)$ is perpendicular to vector $\boldsymbol{t}$, connecting i-th joint to end-effector

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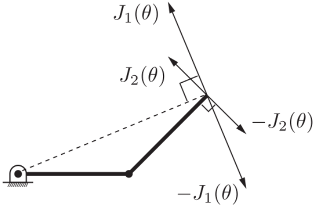

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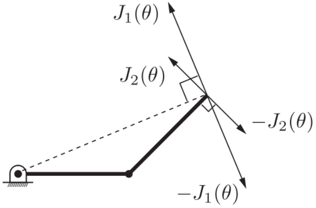

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  - $\boldsymbol{t}_{JE}$ - translation part of $T_{JE} \in SE(2)$

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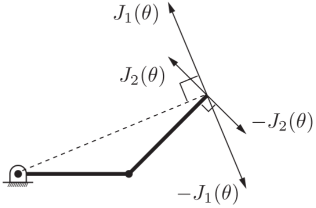

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  - $\boldsymbol{n} = R(90)\boldsymbol{t}_{JE}$ - perpendicular vector

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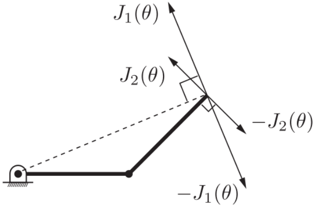

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  - $\boldsymbol{n}_S = R_{SJ}\boldsymbol{n}$ - change of reference frame

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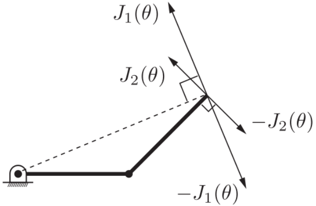

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  - For prismatic joints: $\boldsymbol{n}_S = R_{SJ}\boldsymbol{a}$
  - $\boldsymbol{a}$ is axis of translation

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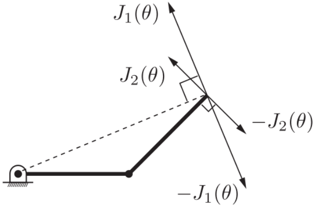

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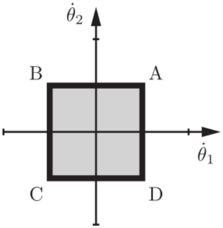
  - For prismatic joints: $\boldsymbol{n}_S = R_{SJ}\boldsymbol{a}$
  - $\boldsymbol{a}$ is axis of translation
- Rotation part
  - 1 for revolute joints
  - 0 for prismatic joints

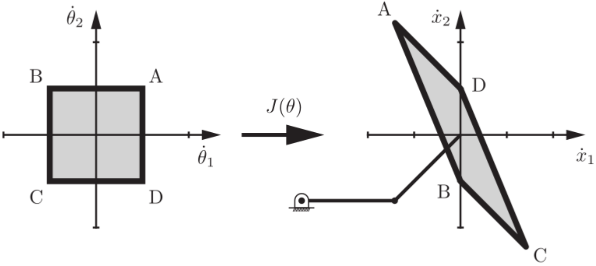
Jacobian application - velocity limits

- $\dot{\boldsymbol{x}} = J(\boldsymbol{q})\dot{\boldsymbol{q}}$
- Velocity limits are given for each joint
  - configuration independent



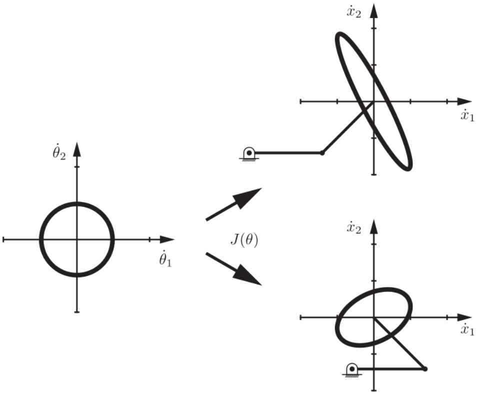
Jacobian application - velocity limits

- $\dot{\boldsymbol{x}} = J(\boldsymbol{q})\dot{\boldsymbol{q}}$
- Velocity limits are given for each joint
  - configuration independent
- What are the velocity we can achieve with end-effector?
  - depends on configuration
  - use jacobian to map joint-space velocity to task-space velocity



Manipulability ellipsoid

- Unit circle in joint velocity space, *i.e.* $\|\dot{\boldsymbol{q}}\| = 1$
- Mapping through Jacobian to ellipsoid in end-effector space
- Closer the ellipsoid is to sphere, more easily can end-effector move in arbitrary direction



How to compute manipulability ellipsoid

$$1 = \|\dot{\boldsymbol{q}}\|$$

How to compute manipulability ellipsoid

$$
\begin{aligned}
1 &= \|\dot{\boldsymbol{q}}\| \\
&= \dot{\boldsymbol{q}}^\top \dot{\boldsymbol{q}}
\end{aligned}
$$

How to compute manipulability ellipsoid

- If $J(\boldsymbol{q})$ is non-singular

$$\begin{aligned}
1 &= \|\dot{\boldsymbol{q}}\| \\
&= \dot{\boldsymbol{q}}^\top \dot{\boldsymbol{q}} \\
&= \left(J(\boldsymbol{q})^{-1}\dot{\boldsymbol{x}}\right)^\top \left(J(\boldsymbol{q})^{-1}\dot{\boldsymbol{x}}\right)
\end{aligned}$$

How to compute manipulability ellipsoid

- If $J(\boldsymbol{q})$ is non-singular

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- If $J(\boldsymbol{q})$ is non-singular
- Solution to $\boldsymbol{u}^\top A^{-1}\boldsymbol{u} = 1$ is ellipsoid
  - eigen vectors of A show directions of principal axes of the ellipsoid
  - square roots of eigen values are lengths of the principal axis

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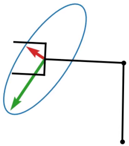
Manipulability ellipsoid example

- 2 DoF robot, translation only, $\mathrm{eig}(JJ^\top)$



How close we are to singularity?

- Condition number of $JJ^\top$
  - $\mu_1 = \frac{\lambda_{\max}(JJ^\top)}{\lambda_{\min}(JJ^\top)} \geq 1$
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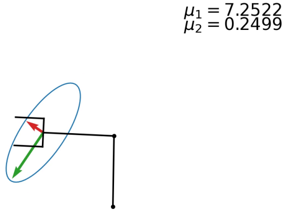
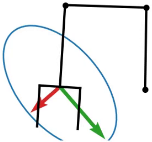


Redundant robots and singularities



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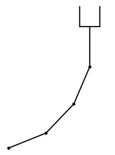

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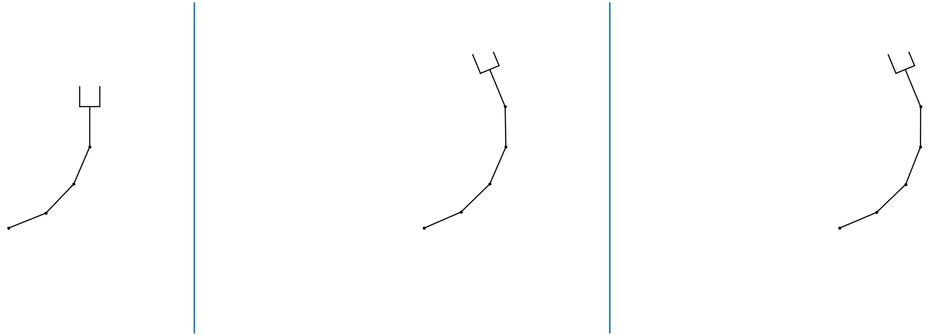
  - there are multiple solutions if we have more DoF



Statics analysis

- Conservation of power: (power at the joints) = (power to move the robot) + (power at the end-effector)

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  - For Panda robot, you can directly command $\boldsymbol{\tau}_{\text{ext}}$

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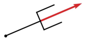

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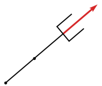

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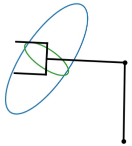
- Singularities (square J, but non-invertible)
  - non-zero null-space

Force ellipsoid

- How easy is to generate force in a given direction.
- Eigen analysis of $(JJ^\top)^{-1}$
  - Blue - manipulability ellipsoid (i.e. $JJ^\top$)
  - Green - force ellipsoid (i.e. $(JJ^\top)^{-1}$)
- Easy motion in a direction $\rightarrow$ difficult to compensate force in that direction
- Close to singularity:
  - area of manipulability ellipsoid $\rightarrow 0$
  - area of force ellipsoid $\rightarrow \infty$



Summary

- Differential kinematics
  - Jacobian and its properties
  - How to compute Jacobian
  - Manipulability ellipsoids
  - How to measure distance to singularity
- Statics
  - Static equilibrium relation of joint torques and task-space forces
  - Force ellipsoids

Laboratory

- Implementation of jacobian computation for planar manipulator
  - Finite difference method
  - Analytical method
- Generation of movement in null-space