

A comparison of three-dimensional rotation formalisms for least-squares and Bayesian inverse kinematics

Appendix C

Ben Serrien, Klevis Aliaj, Todd Pataky

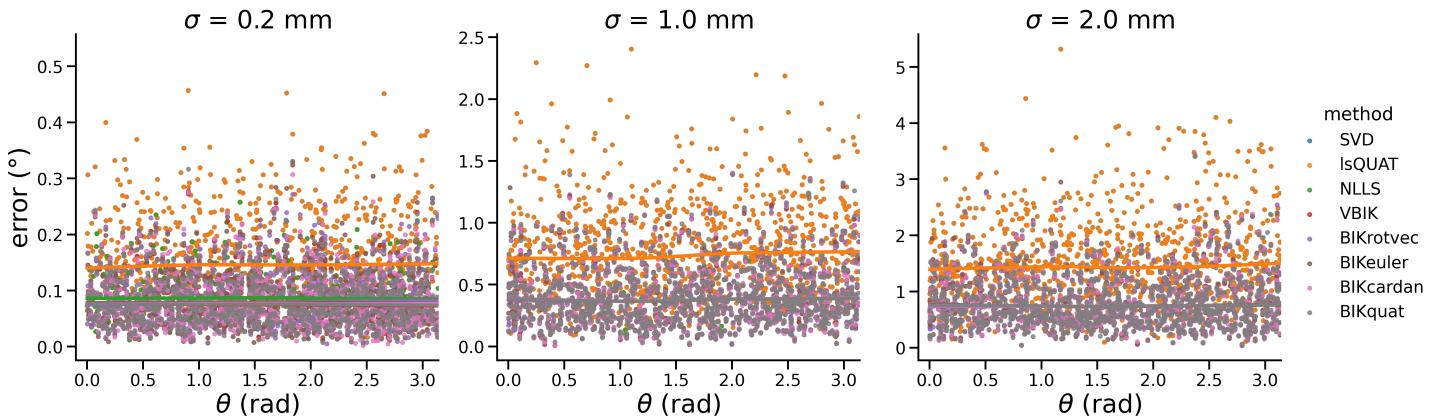


Figure 1: Scatter plots of inverse kinematics estimation errors versus rotation magnitude (θ). Note the different y-axis scales corresponding to different noise levels (σ). The lines are locally weighted scatter plot smoothers (LOESS) representing local averages.

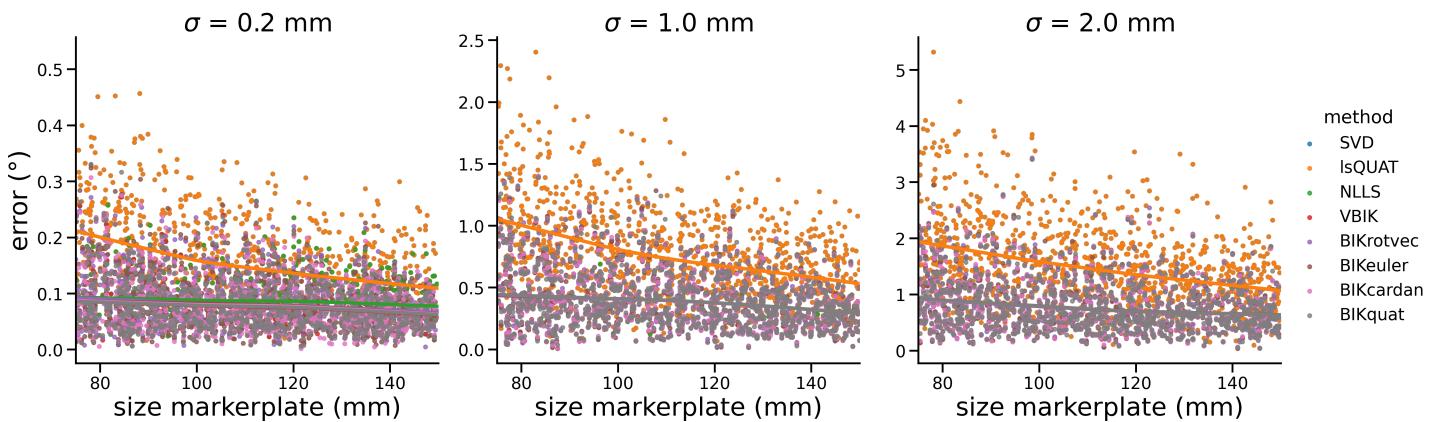


Figure 2: Scatter plots of inverse kinematics estimation errors versus size of the marker plate (size = x indicates a square marker plate of $x^2 \text{ mm}^2$). Note the different y-axis scales corresponding to different noise levels (σ). The lines are locally weighted scatter plot smoothers (LOESS) representing local averages.

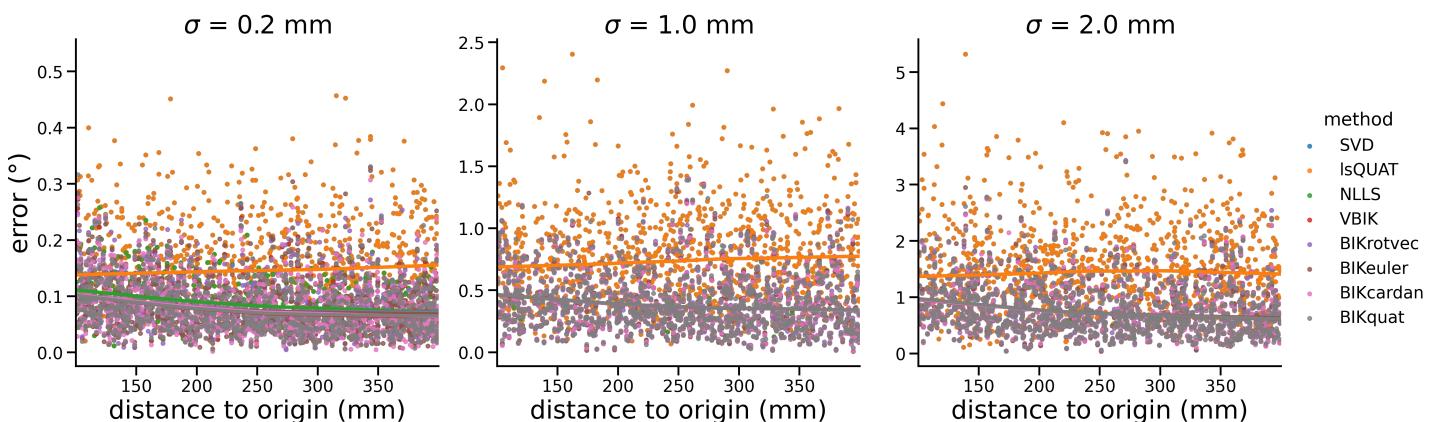


Figure 3: Scatter plots of inverse kinematics estimation errors versus distance of the marker plate centroid to the origin. Note the different y-axis scales corresponding to different noise levels (σ). The lines are locally weighted scatter plot smoothers (LOESS) representing local averages.