Robotics_Mock_Exam

06 February 2021 09:15

Robotics_...

HOCHSCHULE RHEIN-WAAL
Rhine-Waal University of Applied Sciences

Mock Exam

Course of study: Robotics

Examination …

Points:

Duration of examination:

Please write legibly!

Date: ____________________

Name: ____________________

Register No.:____________________

Study Course: ___________________

Hints:

Make sure that you enter your matriculation number in the header of each examination sheet.

Basically, multiple answers to each task or question can be correct. Please mark the box or boxes (☒) with the correct answers or enter the solutions into the appropriate field (___). Wrong answers to multiple choice tasks only lead to a reduction of points within the same task.

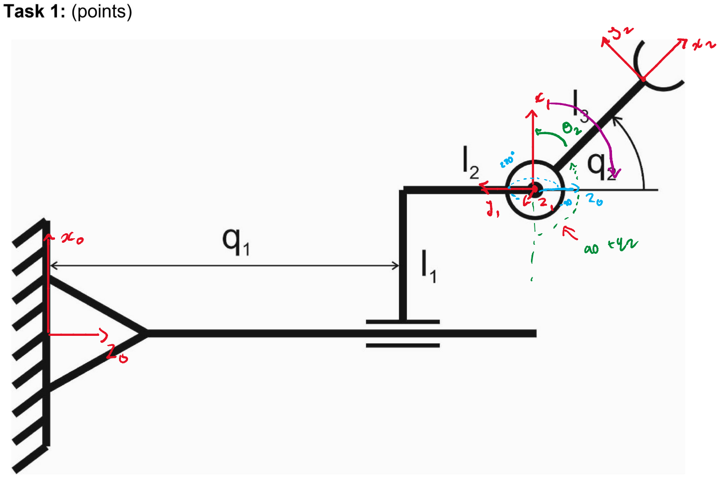
Example:

(2 points)

☐ wrong	☐ wrong	☒ wrong	☒ wrong
☒ right	☐ right	☒ right	☒ right
☐ wrong	☐ wrong	☐ wrong	☒ wrong
☒ right	☒ right	☐ right	☐ right
2 points	1 point	0 points	0 points

Matriculation number.: ____________________

Task 1: (points)



$x_2 - x_1$ about z_1

$-90 + q_2$

A planar robot with two joints is considered. The first joint is a prismatic one, while the second is revolute. Furthermore $q_1 > 0$ and $-\frac{\pi}{2} \leq q_2 \leq \frac{\pi}{2}$ holds.

a) (points)

Draw the coordinate systems according to the Denavit-Hartenberg algorithm into the illustration of the robot under consideration.

b) (points)

Compute the parameters according to the Denavit-Hartenberg algorithm of the robot under consideration.

	1	2
θ	0	$-\frac{\pi}{2} + q_2$
d	$q_1 + L_2$	0
a	l_2	l_3
α	$-\frac{\pi}{2}$	0

Matriculation number.: ____________

c) (points)

Compute the local transformation matrices $\mathbf{A}_i$.

$$A_1 = \begin{bmatrix} 1 & 0 & 0 & l_1 \\ 0 & 0 & 1 & 0 \\ 0 & -1 & 0 & q_1+l_2 \\ 0 & 0 & 0 & 1 \end{bmatrix}$$

0
$q_1 + l_2$
l_1
-90

$$A_2 = \begin{bmatrix} s_{q_2} & c_{q_2} & 0 & l_3 \cdot s_{q_2} \\ -c_{q_2} & s_{q_2} & 0 & -l_3 \cdot c_{q_2} \\ 0 & 0 & 1 & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix}$$

$-\frac{\pi}{2} + q_2$
d 0
a l_3
α 0

$A_1 \cdot A_2$ rows x last column

$$\begin{bmatrix} s_{q_2} & & & l_3 \cdot s_{q_2} + l_1 \\ & & & 0 \\ & & & l_3 \cdot c_{q_2} + q_1 + l_2 \end{bmatrix}$$

Hint: $\cos\left(x - \frac{\pi}{2}\right) = \sin(x)$, $\quad \sin\left(x - \frac{\pi}{2}\right) = -\cos(x)$

d) (points)

Compute the forward kinematics of the robot under consideration.

$x =$ $l_3 \cdot s_{q_2} + l_1$

$y =$ 0

$z =$ $l_3 \cdot c_{q_2} + q_1 + l_2$

$x = l_3 \cdot s_{q_2} + l_1 \Rightarrow q_2 = \sin^{-1}\left(\frac{x - l_1}{l_3}\right)$

$z = l_3 \cdot c_{q_2} + q_1 + l_2 \quad q_1 = z - l_2 - l_3 \cdot \sqrt{1 - \left(\frac{x - l_1}{l_3}\right)}$

e) (points)

Compute the inverse kinematics of the robot under consideration.

$q_1 =$ $z - l_2 - l_3 \cdot q_2$

$q_2 =$ $\sin^{-1}\left(\frac{x - l_1}{l_3}\right)$

Matriculation number.: ____________________

f) (points)

Compute the 2x2 Jacobian matrix of the robot under consideration.

$$\mathbf{J} = \begin{array}{cc} & \begin{array}{cc} q_1 & \quad q_2 \end{array} \\ \begin{array}{c} y_1 - \\ y_2 - \end{array} & \begin{bmatrix} 0 & l_3 \cdot \cos q_2 \\ 1 & -l_3 \cdot \sin q_2 \end{bmatrix} \end{array}$$

$$\begin{matrix} \frac{\delta f_x}{\delta q_1} & \frac{\delta f_x}{\delta q_2} \\ \frac{\delta f_y}{\delta q_1} & \frac{\delta f_y}{\delta q_2} \end{matrix}$$

d) (points)

Calculate possible singular configurations of the robot under consideration.

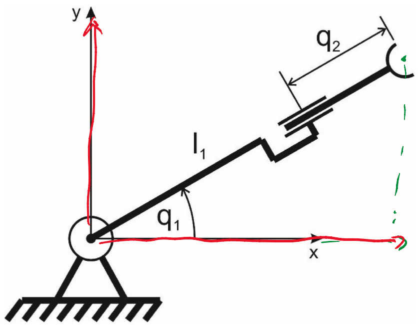
$\det(J) = 0 = l_3 \cdot \cos q_2$

$q_2 = \pm \frac{\pi}{2}$

Explanatory statement: Boundary singularity

Matriculation number.: ____________________

Task 2: (points)



x_e, y_e

$(l_1 + q_2) \times \cos q_1 = x_e$

$(l_1 + q_2) \times \sin q_1 = y_e$

A planar robot with a rotational and a prismatic joint is considered.

a) (points)

Compute the Jacobian matrix of the system under consideration.

$$\mathbf{J} = \begin{array}{c} \\ f_x \\ f_y \end{array} \begin{array}{c} \begin{array}{cc} q_1 & q_2 \end{array} \\ \begin{bmatrix} -(l_1+q_2)\sin q_1 & \cos q_1 \\ (l_1+q_2)\cos q_1 & \sin q_1 \end{bmatrix} \end{array}$$

b) (points)

For a current configuration $\boldsymbol{q} = \begin{bmatrix} \frac{\pi}{4} & \frac{1}{4} \end{bmatrix}'$, $\dot{x} = \begin{bmatrix} 1 & \frac{1}{2} \end{bmatrix}'$ and $l_1 = \frac{3}{4}$ holds. Compute the appropriate joint velocities.

$\rightarrow \dot{x} = J(q) \cdot \dot{q}$

$\rightarrow \dot{q} = J^{-1} \cdot \dot{x}$

$$\begin{bmatrix} -\frac{\sqrt{2}}{2} & \frac{\sqrt{2}}{2} \\ \frac{\sqrt{2}}{2} & \frac{\sqrt{2}}{2} \end{bmatrix}$$

$$\frac{1}{\det(A)} \cdot \begin{bmatrix} \frac{\sqrt{2}}{2} & -\frac{\sqrt{2}}{2} \\ -\frac{\sqrt{2}}{2} & -\frac{\sqrt{2}}{2} \end{bmatrix}$$

$$\begin{bmatrix} -\frac{\sqrt{2}}{2} & \frac{\sqrt{2}}{2} \\ \frac{\sqrt{2}}{2} & \frac{\sqrt{2}}{2} \end{bmatrix} \begin{bmatrix} 1 \\ \frac{1}{2} \end{bmatrix} = \begin{bmatrix} -\frac{\sqrt{2}}{4} \\ \frac{3}{4}\sqrt{2} \end{bmatrix}$$

$\dot{y} = J \dot{q} \qquad \times J^T$

$J^T \dot{y} = J^T J \cdot \dot{q}$

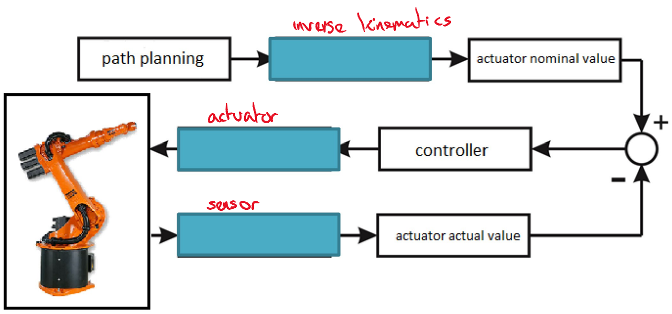
$\dot{q} = (J^T J)^{-1} \cdot J^T \cdot \dot{y}$

$\dot{q}_1 =$ $-\frac{\sqrt{2}}{4}$ $\leftarrow$

$\dot{q}_2 =$ $\frac{3}{4}\sqrt{2}$ $\leftarrow$

Matriculation number.: ____________________

Task 3: (points) Label all blocks in the diagram



Task 4: (points)

Is the given matrix a rotation matrix (give an explanatory statement)?

$$R = \begin{bmatrix} -1 & 0 & 0 \\ 0 & 0 & -1 \\ 0 & 1 & 0 \end{bmatrix} \qquad \begin{bmatrix} -1 & 0 & 0 \\ 0 & 0 & 1 \\ 0 & -1 & 0 \end{bmatrix} = R^T$$

$$R^{-1} = \frac{1}{-1} \begin{pmatrix} +1 & -0 & +0 \\ -0 & +0 & -1 \\ +0 & -1 & +0 \end{pmatrix}^T = \frac{1}{-1} \begin{pmatrix} 1 & 0 & 0 \\ 0 & 0 & -1 \\ 0 & 1 & 0 \end{pmatrix}$$

$$R^{-1} = \begin{pmatrix} -1 & 0 & 0 \\ 0 & 0 & 1 \\ 0 & -1 & 0 \end{pmatrix} = R^T$$

∴ is a rotation matrix

Matriculation number.: ____________________

Task 5: (42 points)

1.) (2 points)

The values of the joint variables for a given end effector pose are calculated by use of

- [x] the inverse kinematics.
- [ ] the recursive Newton-Euler-algorithm.
- [ ] the Jacobian matrix.
- [ ] a path planning method.

2.) (2 points)

How many degrees of freedom does the end effector of a spatial robot have at maximum?

- [ ] 3
- [ ] 2
- [x] 6
- [ ] 8

3.) (2 points)

What are the properties of a rotation matrix **R**?

- [x] **R** is square.
- [x] **R** is orthogonal.
- [ ] **R** is diagonal.
- [ ] **R** is singular.

4.) (2 points)

A homogenous transformation matrix describes

- [x] a compact description of a rigid body transformation.
- [ ] an algorithm for the derivation of the Jacobian.
- [ ] the mapping of a non-square matrix into the nullspace.
- [ ] an algorithm for the derivation of the pseudo-inverse.

5.) (2 points)

How many solutions does the forward kinematics of a spatial serial manipulator usually have?

- [ ] 3
- [ ] 6
- [x] 1
- [ ] none

6.) (2 points)

The mapping of the joint velocities onto the end effector velocities by use of a Jacobian is

- [x] linear.
- [ ] non-linear.
- [ ] singular.
- [ ] proportional.

Matriculation number.: ____________________

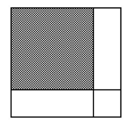
7.) (2 points)

How many independent parameters does a rotation matrix have at maximum to describe the orientation of a coordinate system with respect to another coordinate system?

- ☐ 9
- ☐ 1
- ☒ 3
- ☐ 0

8.) (2 points)

The upper left 3x3 sub-matrix of a homogenous transformation matrix has the meaning of a



- ☐ translation.
- ☒ rotation.
- ☐ bias.
- ☐ scaling.

9.) (2 points)

The determinant of a rotation matrix for a „right-handed“ system is equal to

- ☒ 1.
- ☐ 0.
- ☐ -1.
- ☐ $-\pi$.

10.)(2 points)

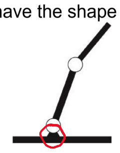
The norm of a row or a line of a rotation matrix is equal to

- ☒ 1.
- ☐ π.
- ☐ $\frac{\pi}{2}$.
- ☐ -1.

11.) (2 points)

The workspace of a plain robot with two rotational joints can have the shape of

- ☐ a circle.
- ☒ a circular ring.
- ☐ a square.
- ☐ an ellipse.



12.) (2 points)

In which cases is the pseudo-inverse of a Jacobian typically used?

- ☐ The Jacobian is square and diagonal.
- ☐ The TCP is outside the workspace.
- ☒ The Jacobian is of non-square type.

Matriculation number.: ____________________

- ☐ The number of joints is larger than the amount of degrees of freedom of the end effector.

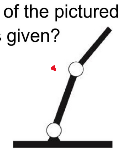
13.) (2 points)

Singularities appear typically if

- ☒ the Jacobian matrix is singular.
- ☒ the robot is in a stretched position.
- ☐ the Jacobian matrix is square.
- ☐ the end effector leaves the planned path.

14.) (2 points)

How many possible solutions does the inverse kinematics of the pictured robot have, assuming only the position of the tool center point is given?



- ☐ one solution
- ☐ no solution
- ☒ two solutions
- ☐ infinite amount of solutions

15.)(2 points)

What is the dimension of the Jacobian of a robot with 7 actuators and 6 end effector degrees of freedom?

- ☐ 7x6
- ☐ 6x7x6
- ☒ 6x7
- ☐ 6x6

16.)(2 points)

How many actuators does a robot need at least, assuming three independent degrees of freedom for the end effector are required?

- ☐ 1 actuator
- ☐ 6 actuators
- ☒ 3 actuators
- ☐ 5 actuators

Good luck!

Matriculation number.: ____________________

Appendix:

Denavit-Hartenberg algorithm

Definition of the coordinate systems:

1. Definition of the initial coordinate system at the base of the robot. The z_0-axis lies within the axis of movement of the first joint in direction of the kinematic chain. Define the x_0- and y_0-axes in order to generate an orthogonal right-handed system.
2. For i=1,…,n-1 do the following steps:
3. The z_i-axis is to arrange in direction of the axis of movement of joint i+1 (rotational or translational joint)
4. The origin of coordinate system lies within the intersection point of the z_i- and z_{i-1}-axes or within the intersection point of the z_i-axis with the collective perpendicular of the z_i- and z_{i-1}- axes
5. In case of an intersection of z_{i-1}- and z_i-axis, the x_i-axis is orthogonal to both z_{i-1}- and z_i-axis. Otherwise the x_i-axis lies in direction of the perpendicular between z_i- and z_{i-1}-axis.
6. Choose the y_i-axis in order to generate an orthogonal right-handed system $(x,y,z)_i$.
7. Definition of the TCP coordinate system: The z_n-axis lies in direction of z_{n-1}-axis. The x_n-axis is orthogonal to both z_n- and z_{n-1}-axis.

Denavit-Hartenberg parameters:

θ_i Angle between x_{i-1}-axis and x_i-axis around the z_{i-1}-axis-

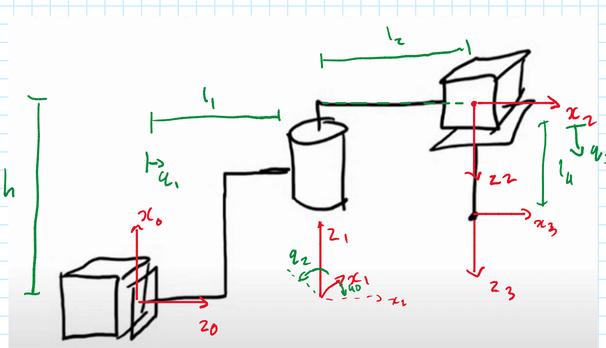
d_i Distance from origin of coordinate system $(x,y,z)_{i-1}$ to the intersection point of z_{i-1}-axis and x_i-axis, measured along the z_{i-1}-axis.

a_i Distance from intersection point of z_{i-1}-axis and x_i-axis to the origin of coordinate system $(x,y,z)_i$, measured along the x_i-axis (or the shortest distance between z_{i-1}-axis and z_i-axis).

α_i Angle between the z_{i-1}-axis and z_i-axis around the x_i-axis.

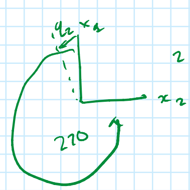
Transformation matrix

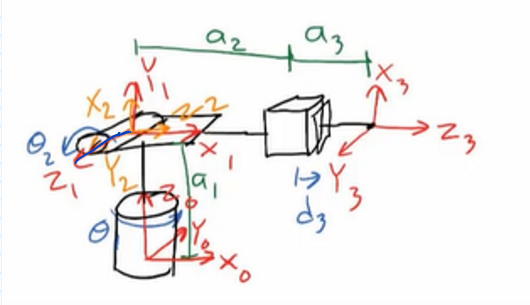
$$\mathbf{A}_i = \mathrm{Rot}_{z,\theta_i}\mathrm{Trans}_{z,d_i}\mathrm{Trans}_{x,a_i}\mathrm{Rot}_{x,\alpha_i} = \begin{bmatrix} \cos(\theta_i) & -\sin(\theta_i)\cos(\alpha_i) & \sin(\theta_i)\sin(\alpha_i) & a_i\cos(\theta_i) \\ \sin(\theta_i) & \cos(\theta_i)\cos(\alpha_i) & -\cos(\theta_i)\sin(\alpha_i) & a_i\sin(\theta_i) \\ 0 & \sin(\alpha_i) & \cos(\alpha_i) & d_i \\ 0 & 0 & 0 & 1 \end{bmatrix}$$



	a	d	α	θ
1	0	l_1+q_1	90	-90
2	l_2	h_1	180	$-90-q_2$
3	0	q_3+l_4	0	0

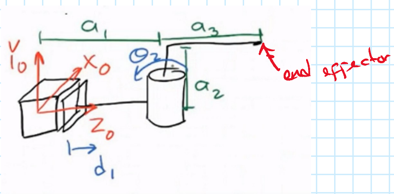
$270-q_2$ $-90-q_2$

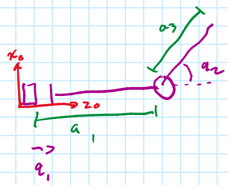




	x_1	z_{i-1}	x_1	z_1 / z_{i-1}
	a	d	α	θ
1	0	a_1	90	θ
2	0	0	90	$90-\theta_2$
3	0	$a_2+a_3+d_3$	0	0

$$A_1 = \begin{pmatrix} c_\theta & -s_\theta \\ s_\theta & \\ 0 & \\ 0 & \end{pmatrix}$$





$x_c = a_3 \cdot \sin q_2 \quad \Rightarrow \quad q_2 = \sin^{-1}\left(\frac{x_1}{a_3}\right)$

$z_c = a_1 + a_3 \cdot \cos q_2 + q_1 \quad q_1 = z_c - a_1 - a_3 \cdot \sqrt{1-\left(\frac{x_1}{a_3}\right)^2}$

$q_1 = z_c - a_1 \mp \sqrt{a_3^2 - x_1^2}$