SCUTTLE Kinematics Guide

revised 2020.09.11

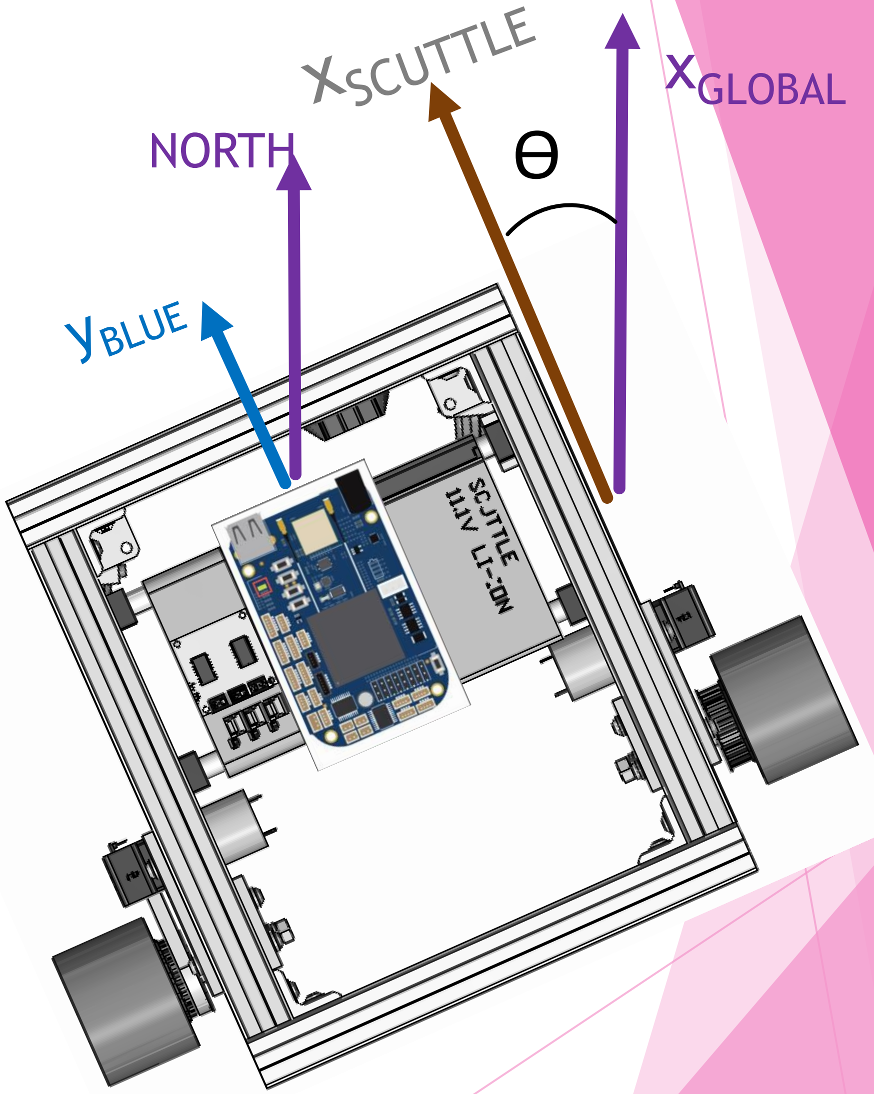
SCUTTLE Coordinates

<u>This slide is for reference.</u>

The beagle circuit board has an IMU with y-axis pointing along the USB port.

The global x- is often decided to be aligned with magnetic North.

The SCUTTLE body-fixed X vector is aligned with the forward direction.



SCUTTLE Kinematics

This guide covers:

- Robot geometry, r, and L
- Important variables: phi, x, y, and theta
- Kinematic equation: convert wheel speeds to chassis speeds
- The time-derivatives of the wheel and chassis displacements
- Rotation matrix to convert body-fixed coordinates to global coordinates

SCUTTLE: a Non-Holonomic System

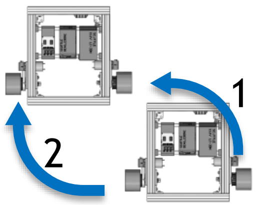
A holonomic robot has the same number (or more) of controllable degrees of freedom as the number of degrees of freedom.

SCUTTLE DOF: (x, y, theta)
CONTROLLABLE DOF: (left motor, right motor)
Mecanum Robot DOF: (x,y,theta)

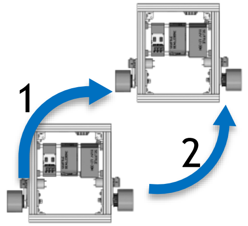
In a non-holonomic system, the final position of the robot depends on the path taken to achieve the movement.

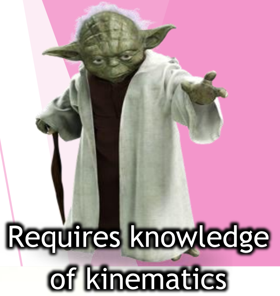
Example:

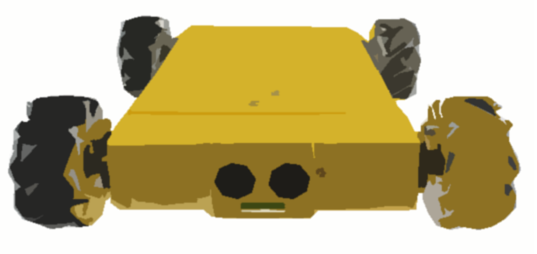
Move right wheel, then left

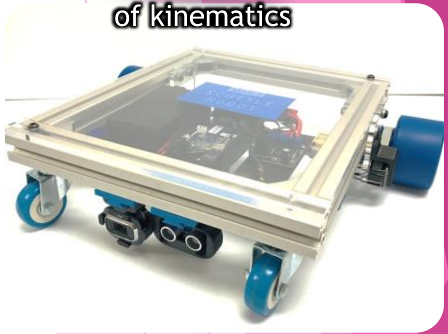


Move left wheel, then Right









Holonomic:

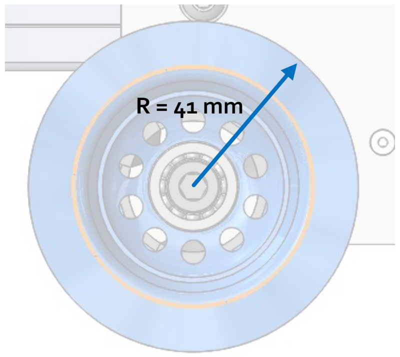
Easier navigation
More parts
Less robust

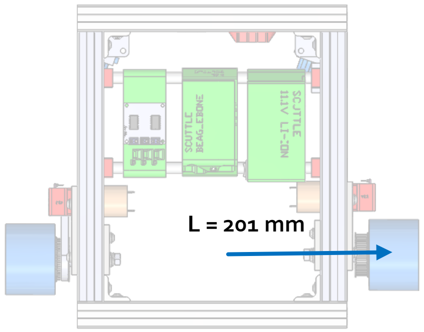
Non-Holonomic:

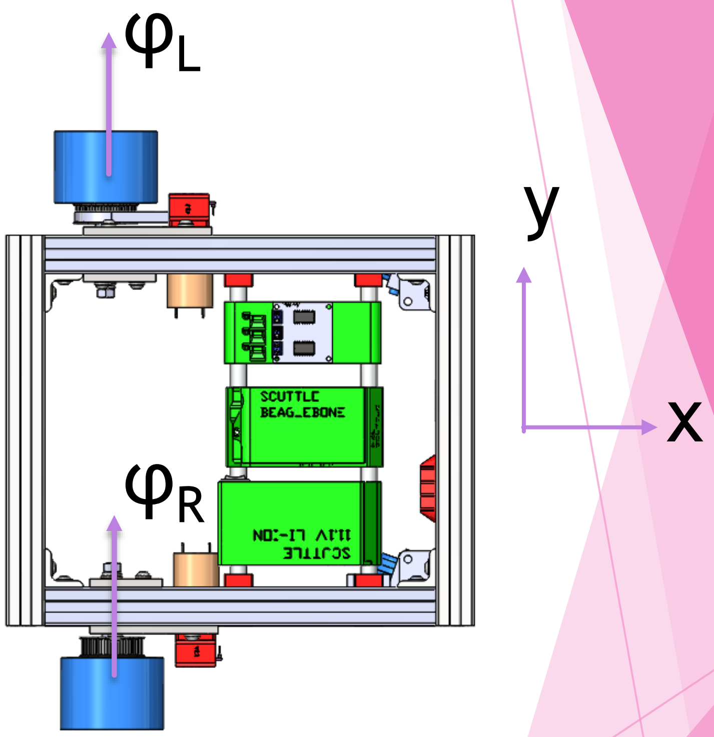
Harder navigation
Fewer parts
More robust

SCUTTLE Kinematics

- The **Chassis Geometry** determines the equations for kinematics.
- The **radius**, r, is the radius of the driven wheel
- The **half-wheelbase**, L, is the space from wheel center to center divided in two





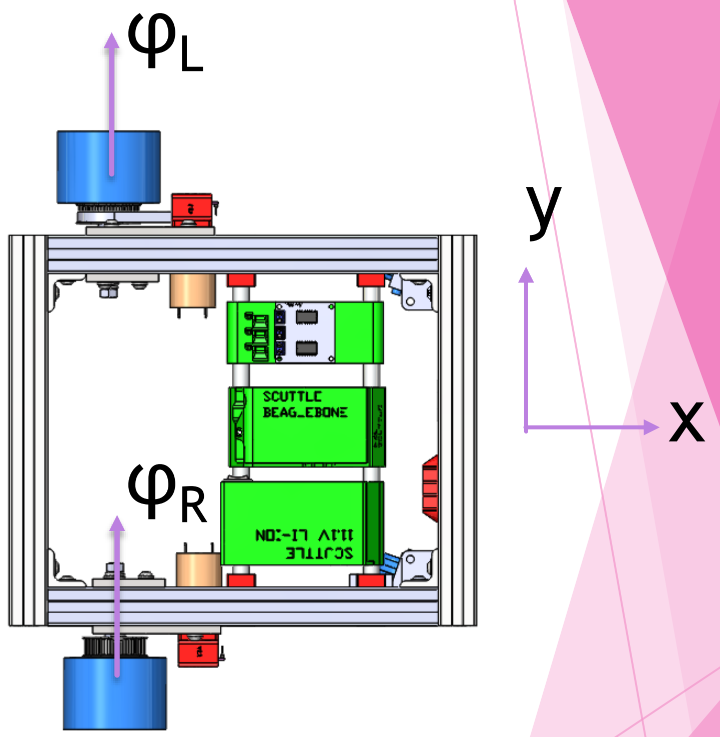


SCUTTLE Kinematics

- **Phi dot** is the derivative of phi with respect to time.

$\dot{\varphi}_L$ = pdl, as in phi_dot_l

$\dot{\varphi}_R$ = pdr, as in phi_dot_r

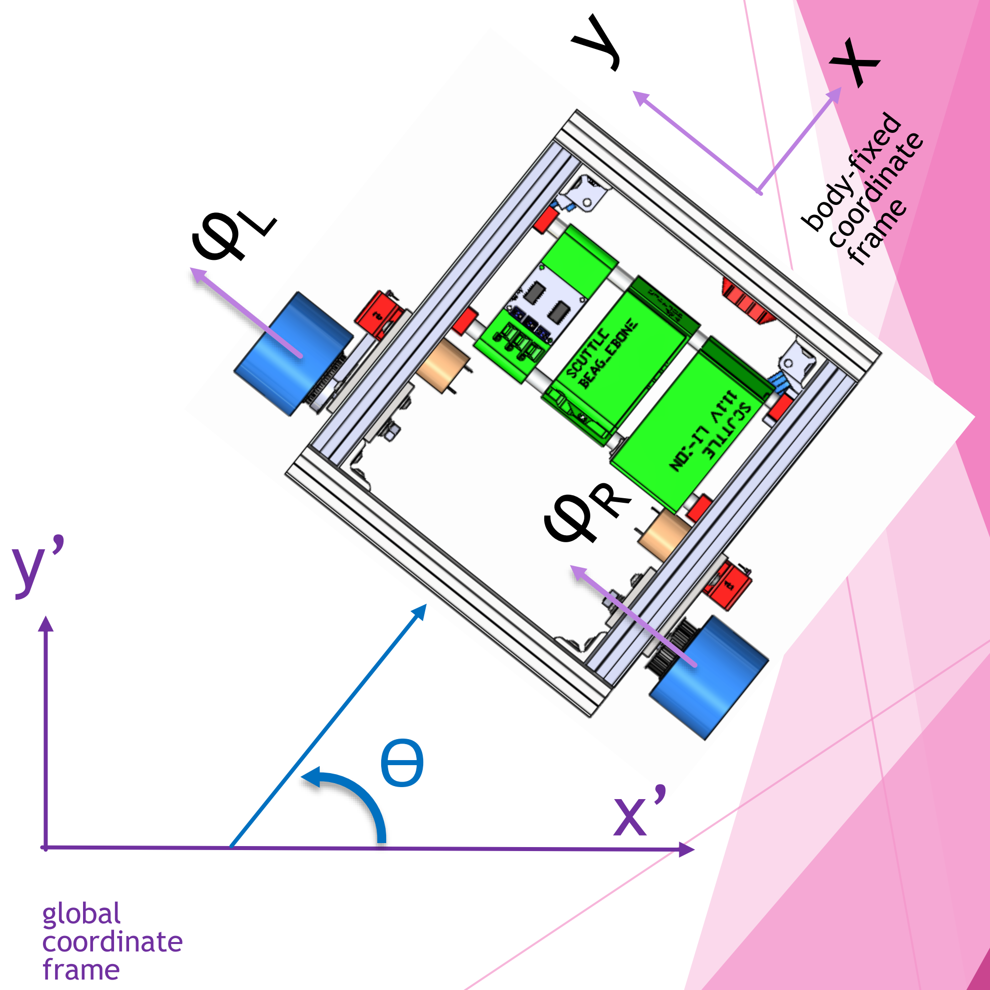



```
phiDots = np.array( [ pdl, pdr ] ) # python syntax
```

SCUTTLE Kinematics

- **Theta** describes the difference between the body-fixed frame and the global frame.
- The **rotation matrix** converts body-fixed coordinates to the global coordinates

$$\begin{bmatrix} x' \\ y' \end{bmatrix} = \begin{bmatrix} \cos(\theta) & -\sin(\theta) \\ \sin(\theta) & \cos(\theta) \end{bmatrix} \begin{bmatrix} x_{bf} \\ y_{bf} \end{bmatrix}$$



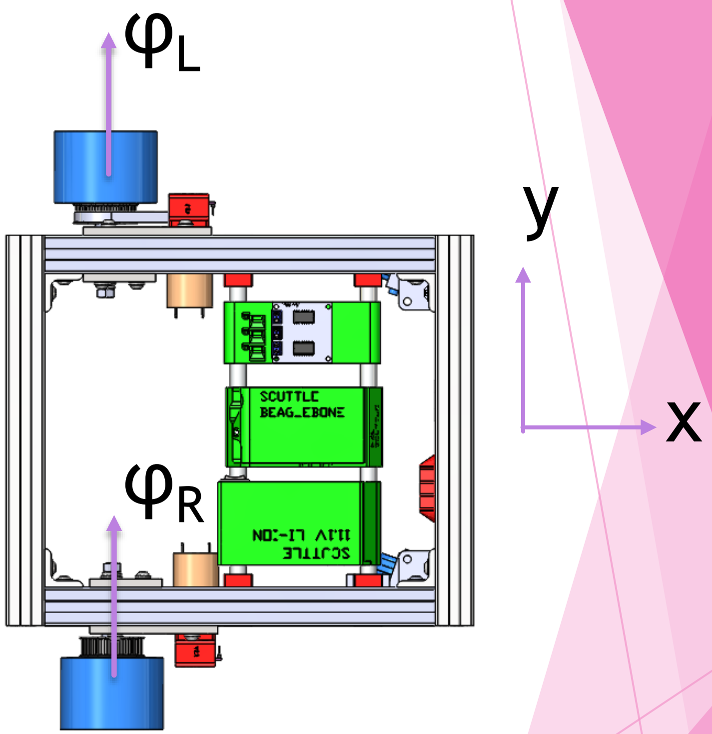
SCUTTLE Kinematics

- Phi is the angle of the wheel.
  - It is used to define incremental changes in wheel position and to calculate wheel speeds

- The x,y coordinate system has x pointing forward on the bot.
  - Positive movement of both phi’s result in positive movement of the robot along the x-direction

- The Kinematic Equation generates chassis motion information.
  - input the wheel speeds and output the (translational and rotational) chassis speeds

$$\begin{bmatrix} \dot{x} \\ \dot{\theta} \end{bmatrix} = \begin{bmatrix} R/2 & R/2 \\ -R/2L & R/2L \end{bmatrix} \begin{bmatrix} \dot{\varphi}_L \\ \dot{\varphi}_R \end{bmatrix}$$

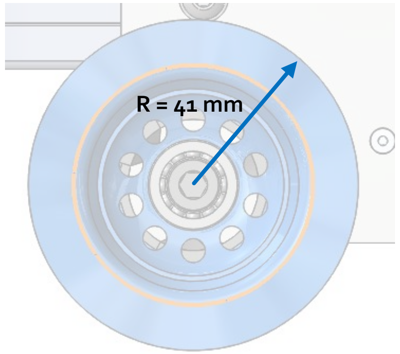


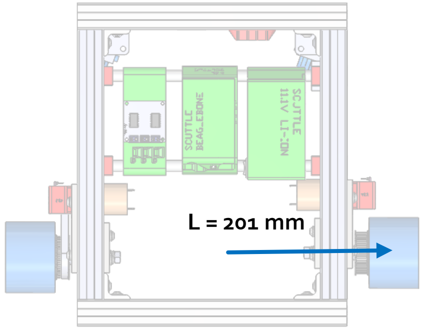
SCUTTLE Kinematics

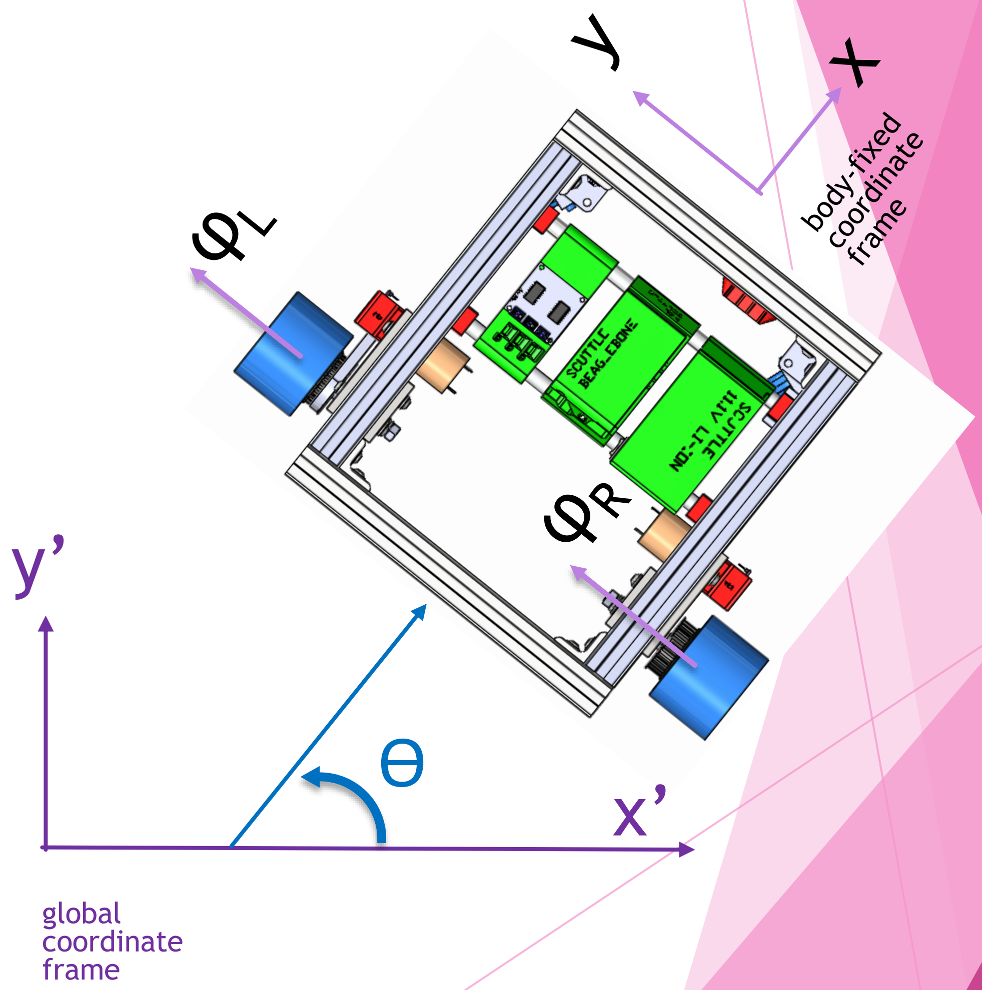
- Inverse Kinematic equation:
  - Input the desired speed and angular speed, and output the left and right wheel speeds.
  - These equations are written in the robot-fixed frame

$$\begin{bmatrix}\dot{\varphi}_L \\ \dot{\varphi}_R\end{bmatrix} = \begin{bmatrix}1/R & -L/R \\ 1/R & L/R\end{bmatrix}\begin{bmatrix}\dot{x} \\ \dot{\theta}\end{bmatrix}$$

matrix multiplication: $[C] = [A][B]$







SCUTTLE Kinematics

- Comparing forward and inverse kinematics:

"Kinematics"
Use the **wheel** speeds to obtain the **chassis** speeds

$$\begin{bmatrix} \dot{x} \\ \dot{\theta} \end{bmatrix} = \begin{bmatrix} R/2 & R/2 \\ -R/2L & R/2L \end{bmatrix} \begin{bmatrix} \dot{\varphi}_L \\ \dot{\varphi}_R \end{bmatrix}$$

"Inverse Kinematics"
Use the **chassis** speeds to obtain the **wheel** speeds

$$\begin{bmatrix} \dot{\varphi}_L \\ \dot{\varphi}_R \end{bmatrix} = \begin{bmatrix} 1/R & -L/R \\ 1/R & L/R \end{bmatrix} \begin{bmatrix} \dot{x} \\ \dot{\theta} \end{bmatrix}$$

SCUTTLE Kinematics (prt 2)

This section will be expanded to discuss navigation

Describing the robot in the inertial (global) frame:

- P0 describes the location of the robot and is defined by the center of the wheelbase.

$$q^I = \begin{bmatrix} x_a \\ y_a \\ \theta \end{bmatrix}$$