

Title of Report

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Preface

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Chapter 1.

Introduction

Hello, here is some text without a meaning. This text should show what a printed text will look like at this place. $\sin^2(\alpha) + \cos^2(\beta) = 1$. If you read this text, you will get no information $E = mc^2$. Really? Is there no information? Is there a difference between this text and some nonsense like “Huardest gefburn”? Kjift – not at all! A blind text like this gives you information about the selected font, how the letters are written and an impression of the look. $\sqrt[n]{a} \cdot \sqrt[n]{b} = \sqrt[n]{ab}$. This text should contain all letters of the alphabet and it should be written in of the original language. $\frac{\sqrt[n]{a}}{\sqrt[n]{b}} = \sqrt[n]{\frac{a}{b}}$. There is no need for special content, but the length of words should match the language. $a\sqrt[n]{b} = \sqrt[n]{a^n b}$.

This is a citation [1]. Hello, here is some text without a meaning. $d\Omega = \sin\vartheta d\vartheta d\varphi$. This text should show what a printed text will look like at this place. If you read this text, you will get no information. Really? Is there no information? Is there a difference between this text and some nonsense like “Huardest gefburn”? Kjift – not at all! A blind text like this gives you information about the selected font, how the letters are written and an impression of the look. $\sin^2(\alpha) + \cos^2(\beta) = 1$. This text should contain all letters of the alphabet and it should be written in of the original language $E = mc^2$. There is no need for special content, but the length of words should match the language. $\sqrt[n]{a} \cdot \sqrt[n]{b} = \sqrt[n]{ab}$.

See Table 1.1 for a floating table and (1.1) for an equation.

$$y = ax + b = cz + d \tag{1.1}$$

a	b	c	d
a	b	c	d
a	b	c	d
a	b	c	d

Table 1.1.: This is a floating table

Chapter 2.

Forward Kinematics - Task 1

Denavit-Hartenberg (DH) is a convention broadly used in robotics. It was introduced in order to standardize the attachmemt of cordinate frames to robots. A robot can be seen as a kinematic chain of rigid bodies. These rigid bodies are called links and are connected with joints. A robot arm is represenetd by a kinematic chain which is a concatenation of several links and joints. If one object is manipulated by one robot the system is called open kinematic chain. If several robots manipulate one object simultaneously the system is called closed kinematic chain. In this task we will focus on open chain robots. Forward kinematics is a way of of calculating the end effector pose based on the joint parameters. The relation from the end effector to the base is done by attaching one frame to the end effector and one to the base of the robot. The relation between those two frames is then determined by the homogenous transformation matrix T_E^B . To make things easier a frame can be attached to each link and then the relation between each consecutive frame can be calculated by T_{i+1}^i . Concatenating all these homogenous Transformations and building their dot product determines the homogenous Transformation from the robot base to end effector:

$$T_E^B = T_0^1 * T_1^2 * ... * T_{i-1}^i \quad (2.1)$$

Denavit-Hartenberg (DH) is a convention which standardizes the attachmemt of cordinate frames to a robot. It is a convention broadly used in the community which makes the application of the recursive formula in 2.1 more intuitive. The DH convention provides rules how to attach the frames to the link. In general the result should be the same if the frames are attached differently to the links as long as every link is considered. In the DH convention four different parameters afe used in order to attach frames to the robot links. The frame of the link i+1 is determined based on the frame of the link i. The placement of a frame is visulaized in 2.1. The followinfg consecutive rules are applied:

- 1 z_i alligns with the rotational axis of joint i+1
- 2 O_i is placed at the intersetion of z_i and the common normal of z_{i-1} and z_i
- 3 $O_{i'}$ is placed at the intersetion of z_{i-1} and the common normal of z_{i-1} and z_i
- 4 x_i alligns with the common normal of z_{i-1} and z_i pointing away from $O_{i'}$
- 5 y_i is chosen according to the right hand rule

The DH convention does not define enough rules to make sure that there is just one

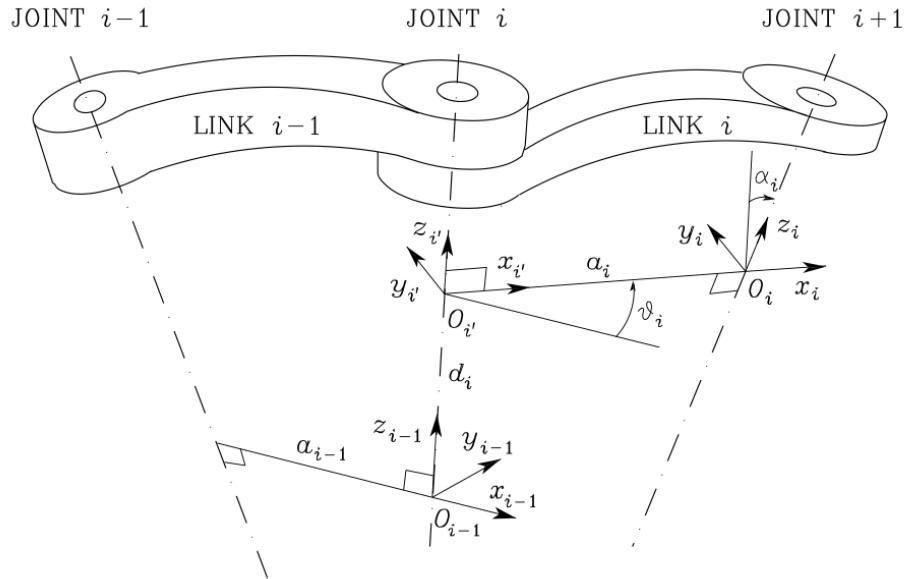


Figure 2.1.: Denavit Hartenberg convention rules

unique solution.

- 1 There is no frame $i-1$ for frame 0 we can not define O_i and x_0 : O_i and x_0 can be defined arbitrarily.
- 2 There is no joint $i+1$ when defining frame n we can not define z_i : z_i is defined parallel to z_{i-1} .

Usually there are some ways of defining those two parameters which make applying the convention easier.

There are some special cases which also do not allow a unique definition of frames:

- 1 z_{i+1} and z_i are parallel: O_i and x_i can be selected arbitrarily.
- 2 z_{i+1} and z_i are parallel: O_i and x_i can be selected arbitrarily.
- 3 joint i is prismatic: x_{i-1} can be selected arbitrarily.

The DH convention makes finding the homogenous transformations especially convenient. After establishing the frames at each joint the four DH parameters can be identified.

- a_i : distance between O_i and $O_{i'}$
- d_i : distance between $O_{i'}$ and O_{i-1} along z_{i-1}
- α_i : angle between z_{i-1} and z_i about x_i
- ϑ_i : angle between x_{i-1} and x_i about z_{i-1}

The parameters a_i and α_i are constant and just depend on the geometry of the link i . Non constant is the parameter d_i if joint i is prismatic and the parameter ϑ_i if joint i is rotational.

Having the four parameters a_i , d_i , α_i , ϑ_i one can write down the homogenous transformations T immediatelly:

$$T_i^{i-1} = \begin{bmatrix} c_{\vartheta_i} & -s_{\vartheta_i}c_{\alpha_i} & s_{\vartheta_i}s_{\alpha_i} & a_ic_{\vartheta_i} \\ s_{\vartheta_i} & c_{\vartheta_i}c_{\alpha_i} & -c_{\vartheta_i}s_{\alpha_i} & a_is_{\vartheta_i} \\ 0 & s_{\alpha_i} & c_{\alpha_i} & d_i \\ 0 & 0 & 0 & 1 \end{bmatrix} \quad (2.2)$$

Chapter 3.

Here Comes Chapter 2

Hello, here is some text without a meaning. $\frac{\sqrt[n]{a}}{\sqrt[n]{b}} = \sqrt[n]{\frac{a}{b}}$. This text should show what a printed text will look like at this place. $a\sqrt[n]{b} = \sqrt[n]{a^n b}$. If you read this text, you will get no information. $d\Omega = \sin\vartheta d\vartheta d\varphi$. Really? Is there no information? Is there a difference between this text and some nonsense like “Huardest gefburn”? Kjift – not at all! A blind text like this gives you information about the selected font, how the letters are written and an impression of the look. This text should contain all letters of the alphabet and it should be written in of the original language. There is no need for special content, but the length of words should match the language. $\sin^2(\alpha) + \cos^2(\beta) = 1$.

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After this fourth paragraph, we start a new paragraph sequence. Hello, here is some text without a meaning. This text should show what a printed text will look like at this place. $\sin^2(\alpha) + \cos^2(\beta) = 1$. If you read this text, you will get no information $E = mc^2$. Really? Is there no information? Is there a difference between this text and some nonsense like “Huardest gefburn”? Kjift – not at all! A blind text like this gives you



Figure 3.1.: NTNU logo

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3.1. Title of section 2

Chapter 4.

Here Comes Chapter 3

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Figure 4.1.: NTNU logo

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Chapter 5.

Conclusion

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References

- [1] J. M. McCarthy and G. S. Soh, *Geometric design of linkages*. SpringerVerlag, 2011, ISBN: 978-1-4614-2767-4.

Appendix A.

Name of Appendix

A.1. This is a section