



Robotics 2

Robots with kinematic redundancy

Part 1: Fundamentals

Prof. Alessandro De Luca

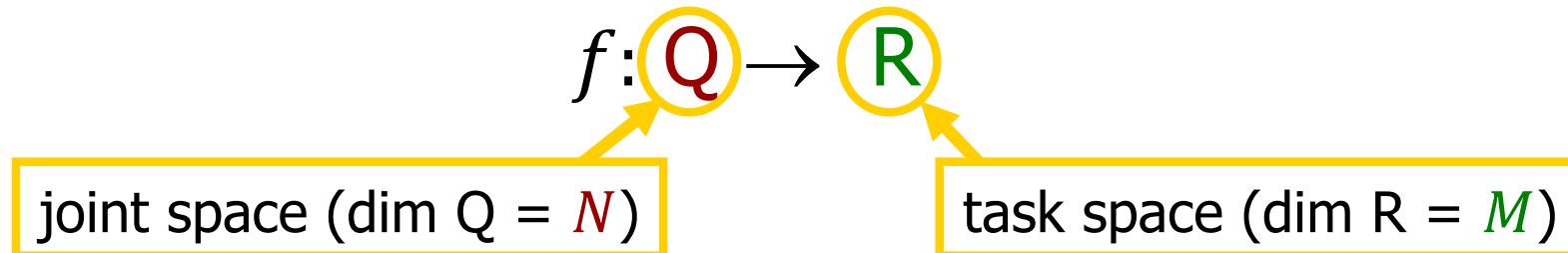
DIPARTIMENTO DI INGEGNERIA INFORMATICA
AUTOMATICA E GESTIONALE ANTONIO RUBERTI





Redundant robots

- direct kinematics of the task $r = f(q)$



- a robot is (kinematically) **redundant** for the task if $N > M$
(more degrees of freedom than strictly needed for executing the task)
- r may contain the position and/or the orientation of the end-effector or, more in general, be any parameterization of the task (even not in the Cartesian workspace)
- “redundancy” of a robot is thus a relative concept, i.e., it holds **with respect to a given task**



Some E-E tasks and their dimensions

TASKS [for the robot end-effector (E-E)]	dimension M
■ position in the plane	→ 2
■ position in 3D space	→ 3
■ orientation in the plane	→ 1
■ pointing in 3D space	→ 2
■ position and orientation in 3D space	→ 6

a planar robot with $N = 3$ joints is **redundant** for the task of **positioning its E-E in the plane ($M = 2$)**, but **NOT** for the task of **positioning AND orienting the E-E in the plane ($M = 3$)**



Typical cases of redundant robots

- 6R robot mounted on a linear track/rail
 - 7 dofs for positioning and orienting its end-effector in 3D space
- 6-dof robot used for arc welding tasks
 - task does not prescribe the final roll angle of the welding gun
- dexterous robotic hands
- multiple cooperating manipulators
- manipulator on a mobile base
- humanoid robots, team of mobile robots ...
- “kinematic” redundancy is not the only type...
 - redundancy of components (actuators, sensors)
 - redundancy in the control/supervision architecture



Uses of robot redundancy

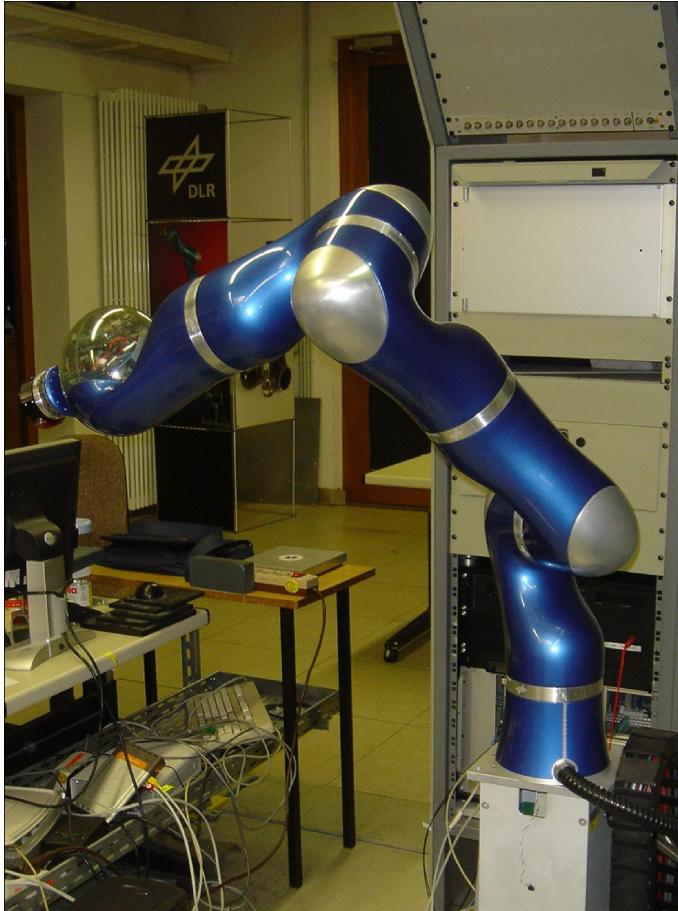
- avoid collision with obstacles (in **Cartesian** space) ...
- ... or kinematic singularities (in **joint** space)
- stay within the admissible joint ranges
- increase manipulability in specified directions
- uniformly distribute/limit joint velocities and/or accelerations
- minimize energy consumption or needed motion torques
- optimize execution time
- increase dependability with respect to faults
- ...



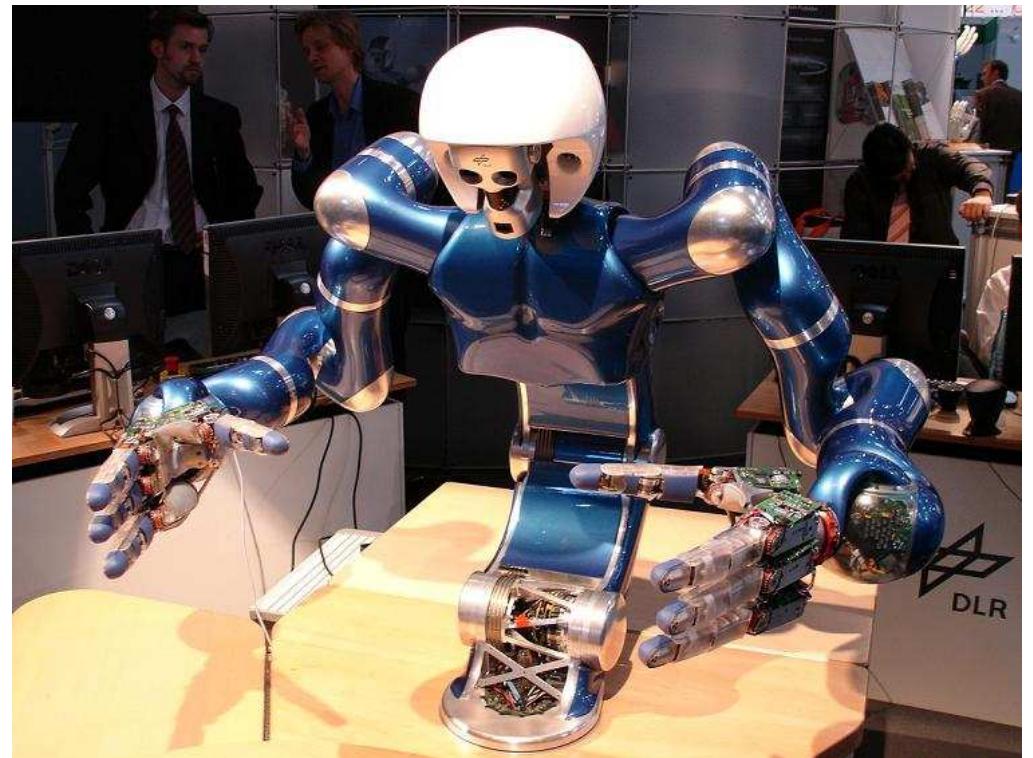
all objectives should be
quantitatively “measurable”



DLR robots: LWR-III and Justin



7R LWR-III lightweight manipulator:
elastic joints (HD), joint torque sensing,
13.5 kg weight = payload



Justin two-arm upper-body humanoid:
43R actuated =

two arms (2×7) + torso (3*)
+ head (2) + two hands (2×12),
45 kg weight

* = one joint is dependent on the motion of the other two



Justin carrying a trailer

[video](#)



LAAS-CNRS

DLR



SIXTH FRAMEWORK PROGRAMME

motion planning for **DLR Justin robot** in the configuration space,
avoiding Cartesian obstacles and using robot redundancy



Dual-arm redundancy



video

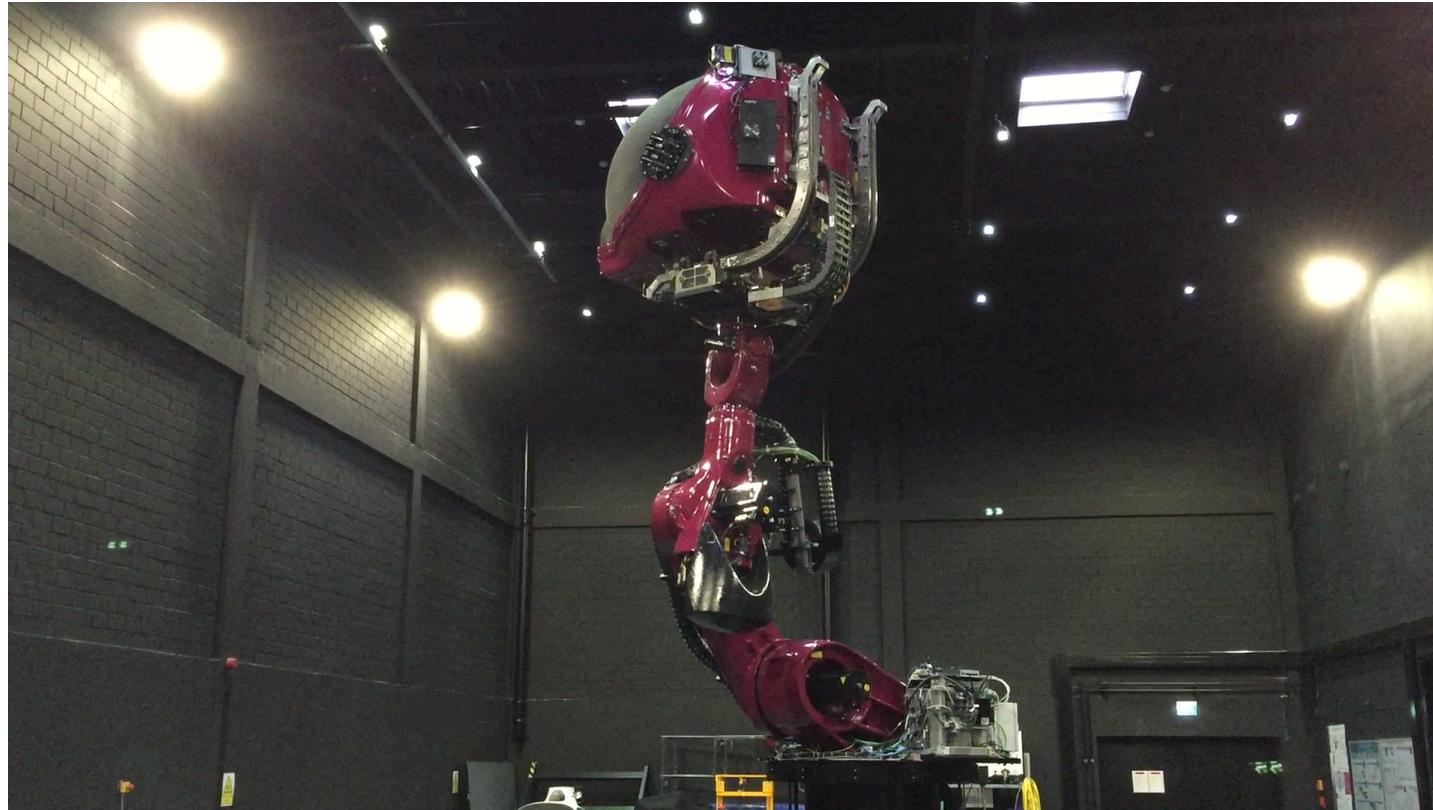
DIS, Uni Napoli

two 6R Comau robots, one mounted on a linear track (+1P)
coordinated 6D motion using the null-space of the right-side robot ($N - M = 1$)



Motion cueing from redundancy

video



Max Planck Institute for Biological Cybernetics, Tübingen

a **6R KUKA KR500** mounted on a linear track (**+1P**) with a sliding cabin (**+1R**),
used as a dynamic emulation platform for human perception ($N - M = 2$)



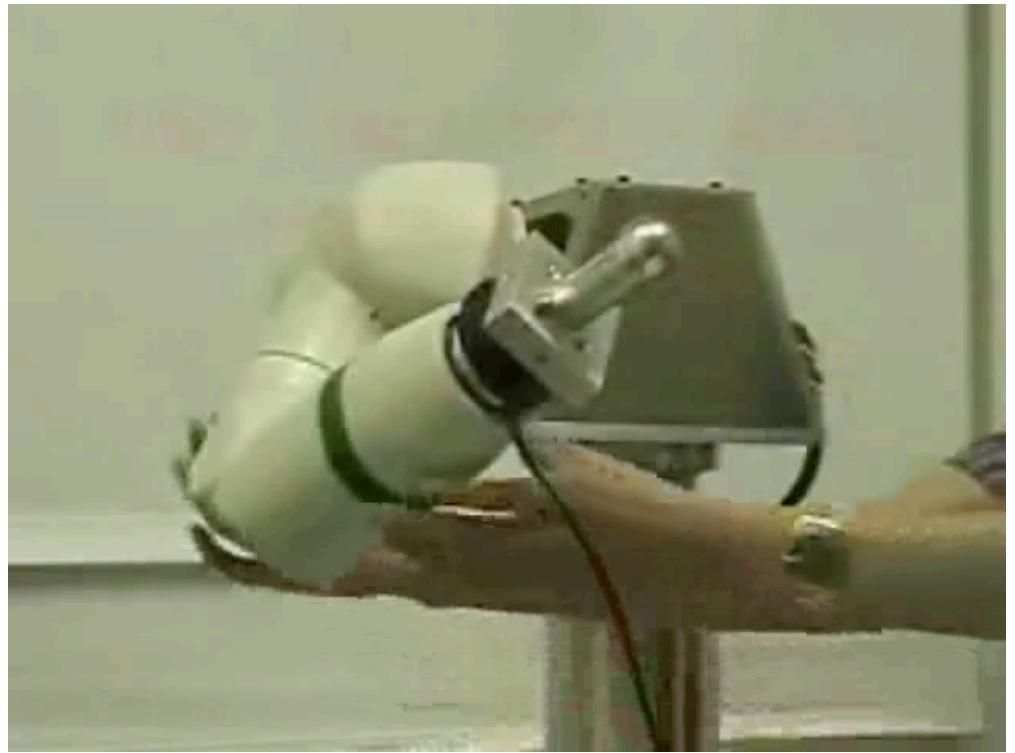
Self-motion

video



8R Dexter: self-motion with constant 6D pose of E-E ($N - M = 2$)

video

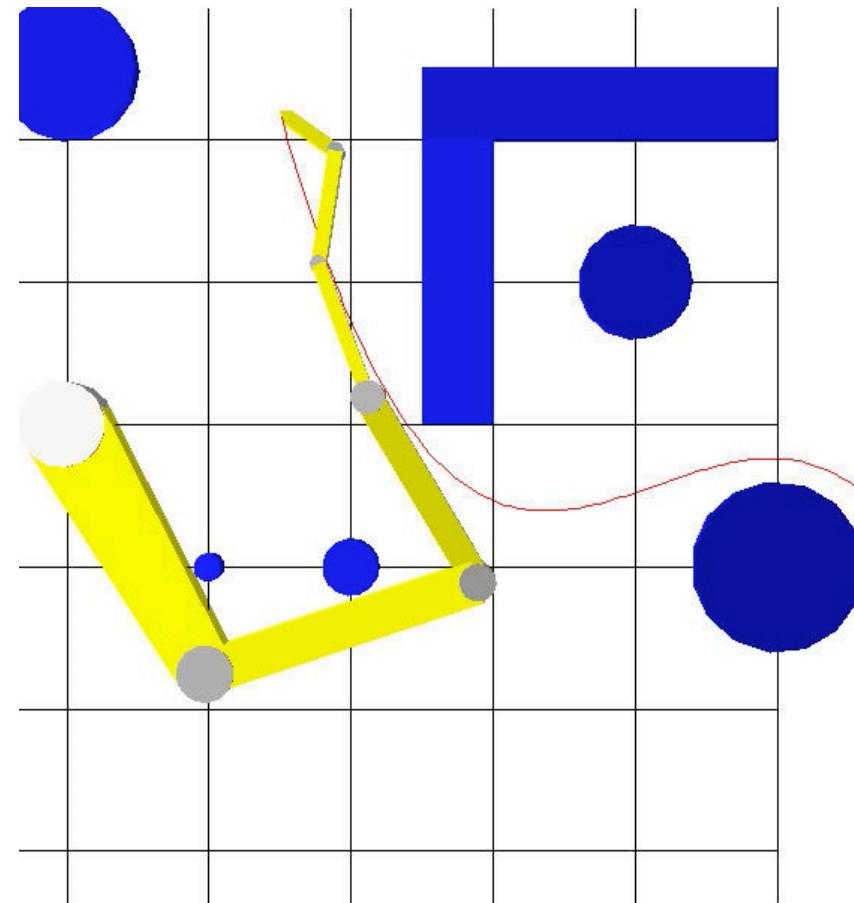


Nakamura's Lab, Uni Tokyo

6R robot with spherical shoulder in compliant tasks for the Cartesian E-E position ($N - M = 3$)



Obstacle avoidance



[video](#)

6R planar arm moving on a given **geometric path** for the E-E ($N - M = 4$)



Disadvantages of redundancy

- potential benefits should be traded off against
 - a greater structural complexity of construction
 - mechanical (more links, transmissions, ...)
 - more actuators, sensors, ...
 - costs
 - more complicated algorithms for **inverse kinematics** and **motion control**

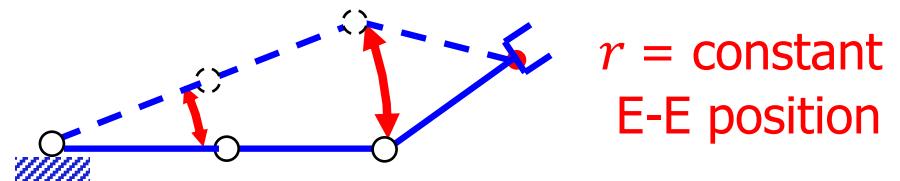


Inverse kinematics problem

- find $q(t)$ that realizes the task: $f(q(t)) = r(t)$ (at all times t)

- **infinite solutions** exist when the robot is redundant
(even for $r(t) = r = \text{constant}$)

$$N = 3 > 2 = M$$



- the robot arm may have “**internal displacements**” that are **unobservable** at the task level (e.g., not contributing to E-E motion)
 - these joint displacements can be chosen so as to **improve/optimize** in some way the behavior of the robotic system
- **self-motion**: an arm reconfiguration in the joint space that does not change/affect the value of the task variables r
- solutions are mainly sought at **differential level** (e.g., **velocity**)

Redundancy resolution

via optimization of an objective function

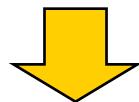


Local methods

given $\dot{r}(t)$ and $q(t)$, $t = kT_s$

optimization of $H(q, \dot{q})$

$\dot{q}(kT_s) \leftarrow$ ON-LINE



$$q((k+1)T_s) = q(kT_s) + T_s \dot{q}(kT_s)$$

discrete-time form

Global methods

given $r(t)$, $t \in [t_0, t_0 + T]$, $q(t_0)$

optimization of $\int_{t_0}^{t_0+T} H(q, \dot{q}) dt$

$q(t)$, $t \in [t_0, t_0 + T]$

↑
OFF-LINE

relatively EASY
(a LQ problem)

quite DIFFICULT
(nonlinear TPBV problems arise)



Local resolution methods

three classes of methods for solving $\dot{r} = J(q)\dot{q}$

1 Jacobian-based methods (here, analytic Jacobian in general!)

among the infinite solutions, one is chosen, e.g., that minimizes a suitable (possibly weighted) norm

2 null-space methods

a term is added to the previous solution so as not to affect execution of the task trajectory, i.e., belonging to the null-space $\mathcal{N}(J(q))$

3 task augmentation methods

redundancy is reduced/eliminated by adding $S \leq N - M$ further auxiliary tasks (when $S = N - M$, the problem has been “squared”)

$$r = f(q) \rightarrow \dot{r} = J(q)\dot{q}$$



1

Jacobian-based methods

we look for a solution to $\dot{r} = J(q)\dot{q}$ in the form

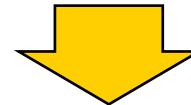
$$J = \boxed{}_N^M$$

$$\dot{q} = K(q)\dot{r}$$

$$K = \boxed{}_M^N$$

minimum requirement for K : $J(q)K(q)J(q) = J(q)$

(\Rightarrow K = generalized inverse of J)



$$\forall \dot{r} \in \mathcal{R}(J(q)) \Rightarrow J(q)[K(q)\dot{r}] = J(q)K(q)J(q)\dot{q} = J(q)\dot{q} = \dot{r}$$

example:

if $J = [J_a \ J_b]$, $\det(J_a) \neq 0$, one such generalized inverse of J is $K_r = \begin{pmatrix} J_a^{-1} \\ 0 \end{pmatrix}$
(actually, this is a **stronger** right-inverse)



Pseudoinverse

$$\dot{q} = J^\#(q)\dot{r}$$

... a very common choice: $K = J^\#$

- $J^\#$ always exists, and is the unique matrix satisfying

$$\begin{array}{ll} JJ^\#J = J & J^\#JJ^\# = J^\# \\ (JJ^\#)^T = JJ^\# & (J^\#J)^T = J^\#J \end{array}$$

- if J is full (row) rank, $J^\# = J^T(JJ^T)^{-1}$; else, it is computed numerically using the SVD (Singular Value Decomposition) of J (`pinv` of Matlab)
- the pseudo-inverse joint velocity is the only that minimizes the norm $\|\dot{q}\|^2 = \dot{q}^T\dot{q}$ among all joint velocities that minimize the task error norm $\|\dot{r} - J(q)\dot{q}\|^2$
- if the task is feasible ($\dot{r} \in \mathcal{R}(J(q))$), there will be no task error



Weighted pseudoinverse

$$\dot{q} = J_W^\#(q)\dot{r} \quad \text{another choice: } K = J_W^\#$$

- the solution \dot{q} minimizes the weighted norm

$$\|\dot{q}\|_W^2 = \dot{q}^T W \dot{q} \quad W > 0, \text{ symmetric} \\ (\text{often diagonal})$$

- if J is full (row) rank, $J_W^\# = W^{-1}J^T(JW^{-1}J^T)^{-1}$
- large weight $W_i \Rightarrow$ small \dot{q}_i
 - larger weights for proximity joints (carrying/moving more “mass”)
 - weights chosen proportionally to the inverse of the joint ranges
- it is NOT a “pseudoinverse” (4th relation does **not** hold),
but it shares similar properties



Singular Value Decomposition (SVD)

- the SVD routine of Matlab applied to J provides two orthonormal matrices $U_{M \times M}$ and $V_{N \times N}$, and a matrix $\Sigma_{M \times N}$ of the form

$$\Sigma = \begin{pmatrix} \sigma_1 & & & \\ & \sigma_2 & & \\ & & \ddots & \\ & & & \sigma_M \end{pmatrix} \left| \begin{array}{c} \\ \\ \\ 0_{M \times (N-M)} \end{array} \right. \quad \begin{aligned} \sigma_1 &\geq \sigma_2 \geq \cdots \geq \sigma_\rho > 0 \\ \sigma_{\rho+1} &= \cdots = \sigma_M = 0 \\ &\text{singular values of } J \end{aligned}$$

where $\rho = \text{rank}(J) \leq M$, so that their product is

$$J = U \Sigma V^T$$

- the columns of U are eigenvectors of $J J^T$ (associated to its non-negative eigenvalues σ_i^2), the columns of V are eigenvectors of $J^T J$
- the last $N - \rho$ columns of V are a basis for the null space of J

$$J v_i = \sigma_i u_i \quad (i = 1, \dots, \rho)$$

$$J v_i = 0 \quad (i = \rho + 1, \dots, N)$$



Computation of pseudoinverses

- **show** that the pseudoinverse of J is equal to

$$J = U\Sigma V^T \quad \Rightarrow \quad J^\# = V\Sigma^\# U^T \quad \Sigma^\# = \begin{pmatrix} \frac{1}{\sigma_1} & & & \\ & \ddots & & \\ & & \frac{1}{\sigma_\rho} & \\ \hline & & & 0_{(M-\rho) \times (M-\rho)} \\ & & & 0_{(N-M) \times M} \end{pmatrix}$$

for any rank ρ of J

- **show** that matrix $J_W^\#$ appears when solving the constrained linear-quadratic (LQ) optimization problem (with $W > 0$, symmetric, and assuming J of full rank)

$$\min \frac{1}{2} \|\dot{q}\|_W^2 \quad \text{s.t.} \quad J(q)\dot{q} - \dot{r} = 0$$

and that the pseudoinverse is a particular case for $W = I$

- **show** that a weighted pseudoinverse of J can be computed by SVD/pinv as

$$J_{aux} = JW^{-1/2} \quad J_W^\# = W^{-1/2} \text{pinv}(J_{aux})$$

applies **equally** to
square and non-square
matrices



Singularity robustness

Damped Least Squares (DLS)

unconstrained
minimization
of a **suitable**
objective function

$$\min_{\dot{q}} H(\dot{q}) = \frac{\mu^2}{2} \|\dot{q}\|^2 + \frac{1}{2} \|\dot{r} - J\dot{q}\|^2$$

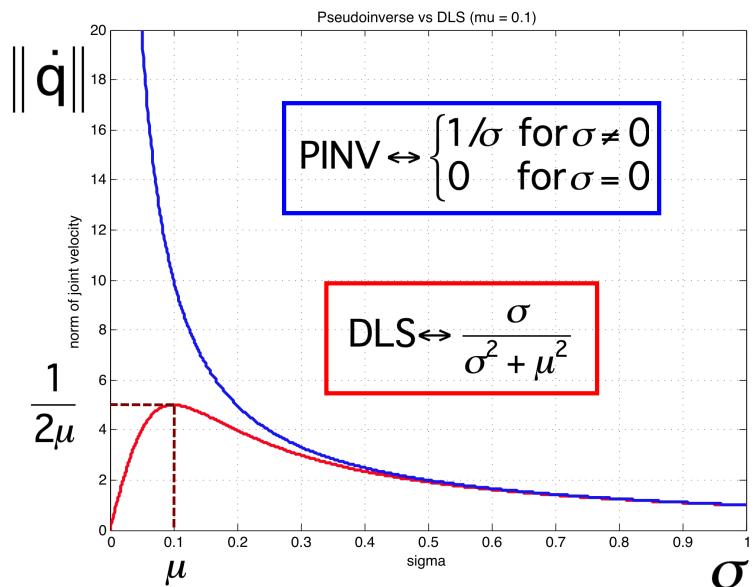
compromise between
large joint velocity
and task accuracy

SOLUTION $\dot{q} = J_{DLS}(q)\dot{r} = J^T(JJ^T + \mu^2 I_M)^{-1}\dot{r}$

- induces a **robust behavior** when crossing **singularities**, but in its basic version gives always a **task error** $\dot{e} = \mu^2(JJ^T + \mu^2 I_M)^{-1}\dot{r}$ (as for $N = M$)
 - J_{DLS} is **not** a generalized inverse K
 - using SVD: $J = U \Sigma V^T \Rightarrow J_{DLS} = V \Sigma_{DLS} U^T$, $\Sigma_{DLS} = \begin{pmatrix} \text{diag} \left\{ \frac{\sigma_i}{\sigma_i^2 + \mu^2} \right\} & \\ \rho \times \rho & 0_{(M-\rho) \times (M-\rho)} \end{pmatrix}$
 - choice of a **variable damping factor** $\mu^2(q) \geq 0$, function of the minimum singular value $\sigma_\rho(q) > 0$ of $J \simeq$ a measure of distance from a singularity (if $\rho = M$) or of further loss of rank (when $\rho < M$)
 - **numerical filtering**: introduces damping **only/mostly** in non-feasible directions for the task (see Maciejewski and Klein, *J of Rob Syst*, 1988)

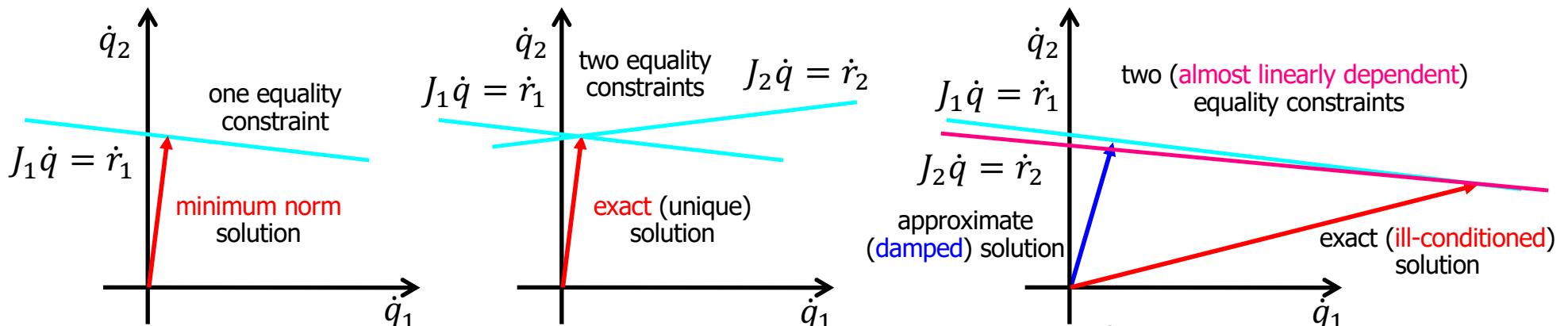


Behavior of DLS solution



- a. comparison of joint velocity norm with PINV (pseudoinverse) or DLS solutions
- in a task direction along a vector u of U , when the associated singular value $\sigma \rightarrow 0$
 - PINV goes to infinity (and then is 0 at $\sigma = 0$)
 - DLS peaks a value of $1/2\mu$ at $\sigma = \mu$ (and then smoothly goes to 0...)

b. graphical interpretation of “damping” effect (here $M = N = 2$, for simplicity)

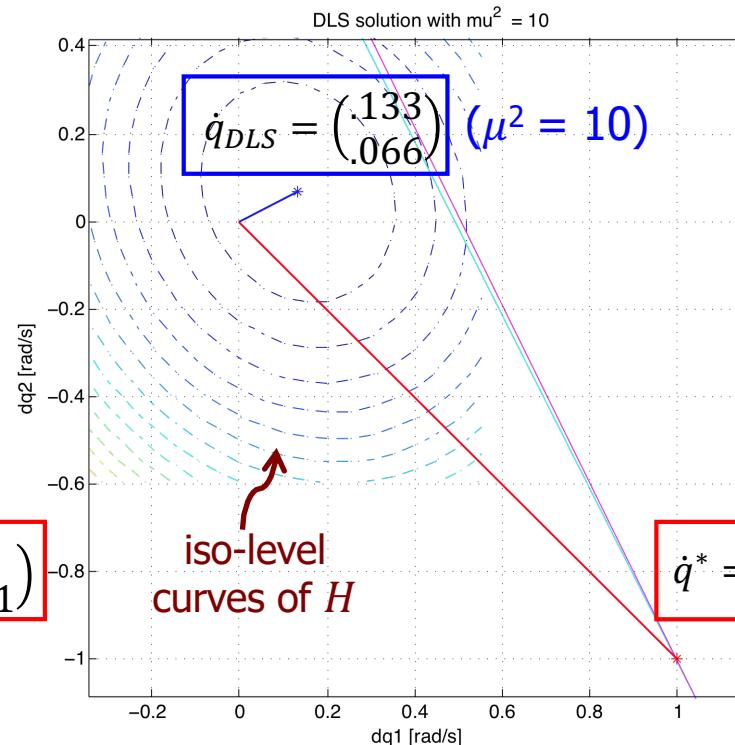
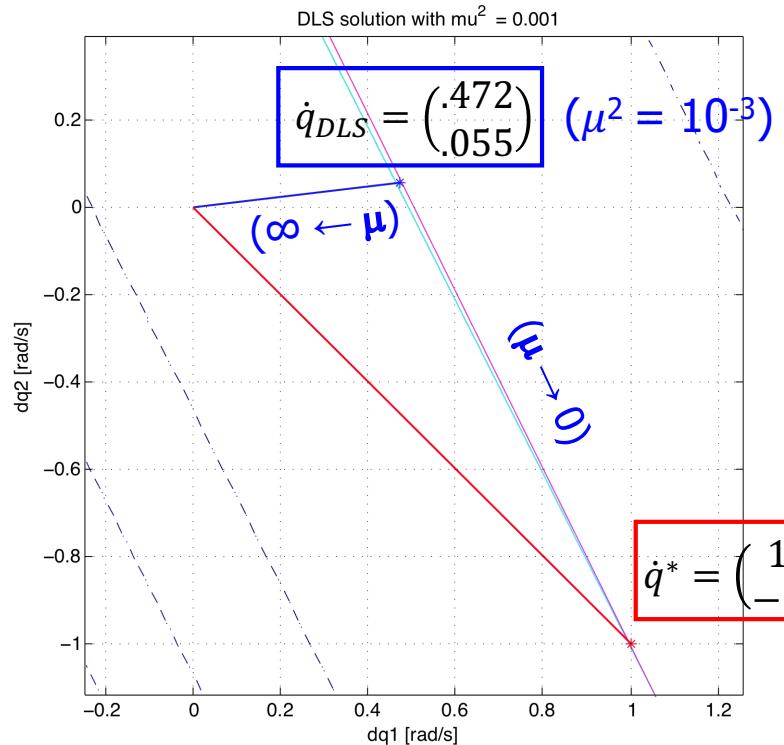


$$H(\dot{q}) = \frac{\mu^2}{2} \|\dot{q}\|^2 + \frac{1}{2} \|\dot{r} - J\dot{q}\|^2$$



Numerical example of DLS solution

planar 2R arm, unit links, close to (stretched) singular configuration $q_1 = 45^\circ, q_2 = 1.5^\circ$



$$\dot{r} = \begin{pmatrix} -1/\sqrt{2} \\ 1/\sqrt{2} \end{pmatrix}$$

$\in \mathcal{R}(J)$ even
@singularity!



exact
solution
($\mu=0$)

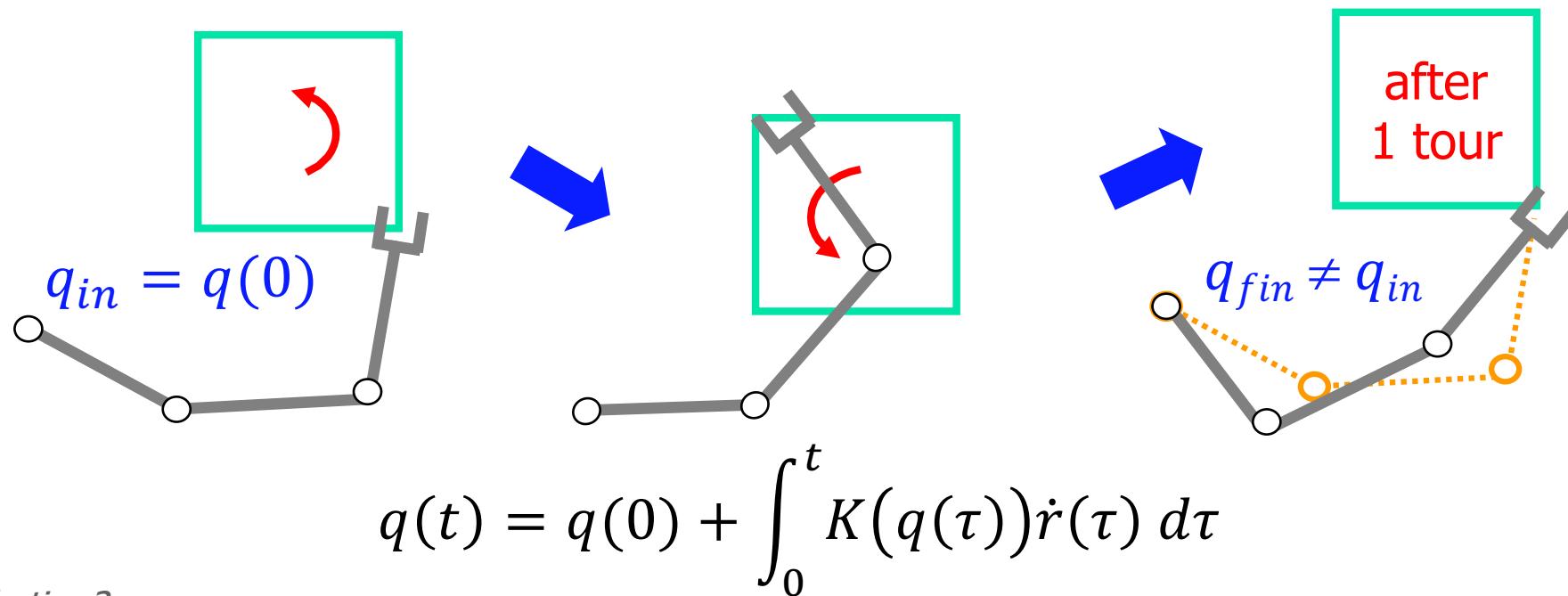
$$H = \frac{\mu^2}{2} \|\dot{q}\|^2 + \frac{1}{2} \|\dot{r} - J\dot{q}\|^2$$

μ^2	0	10^{-4}	10^{-3}	10^{-2}	10
$\ \dot{q}\ $	$\sqrt{2}$.8954	.4755	.4467	.1490
$\ \dot{e}\ $	0	$6.6 \cdot 10^{-3}$	$1.4 \cdot 10^{-2}$	$1.6 \cdot 10^{-2}$.6668
H_{min}	0	$7.7 \cdot 10^{-5}$	$2.2 \cdot 10^{-4}$	$1.2 \cdot 10^{-3}$	$3.4 \cdot 10^{-1}$



Limits of Jacobian-based methods

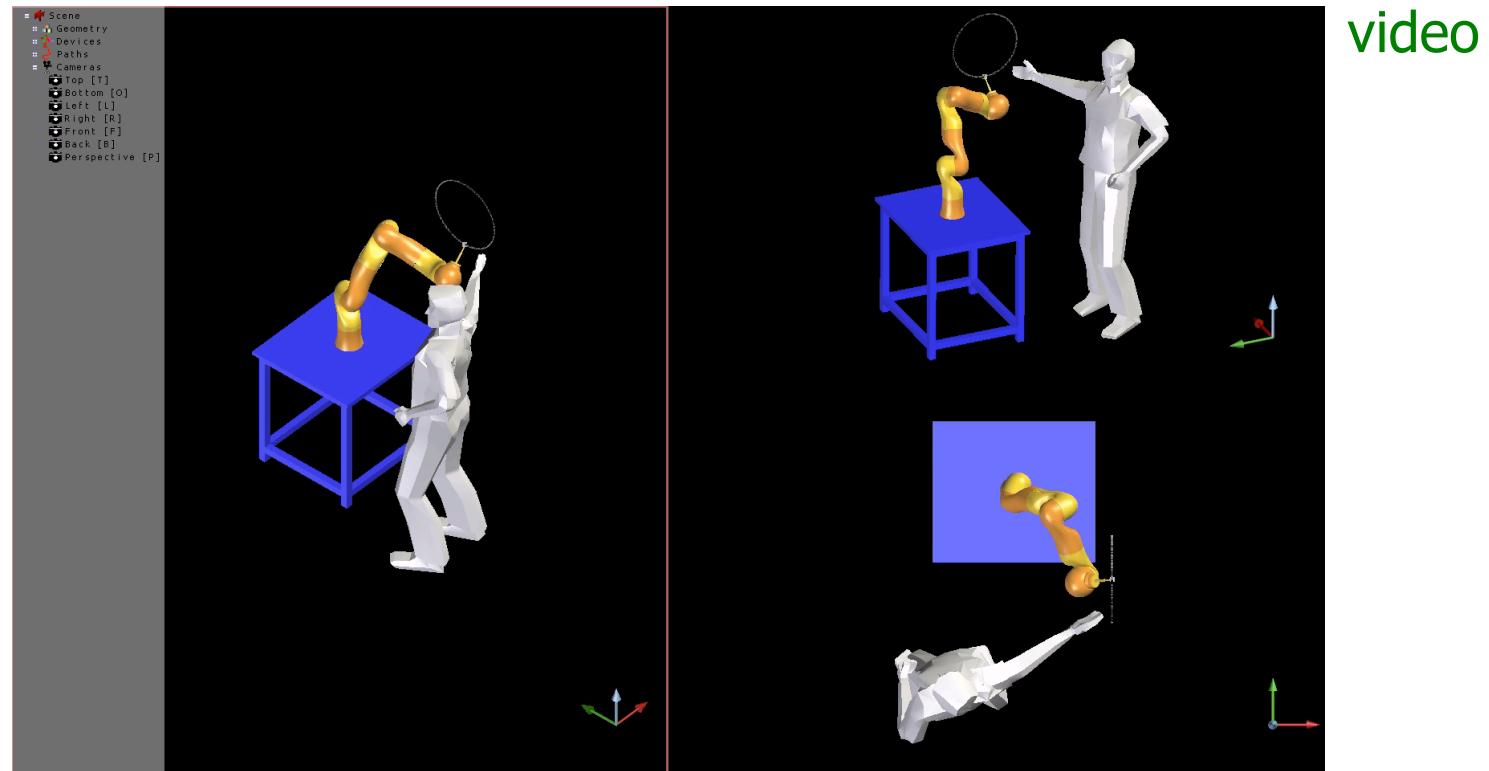
- no guarantee that **singularities** are globally avoided during task execution
 - despite joint velocities are kept to a minimum, this is only a local property and “avalanche” phenomena may occur
- typically lead to **non-repeatable** motion in the joint space
 - cyclic motions in **task space** do not map to cyclic motions in **joint space**





Drift with Jacobian pseudoinverse

- a 7R KUKA LWR4 robot moves in the vicinity of a **human** operator
- we command a cyclic Cartesian path (only in position, $M = 3$), to be repeated **several** times using the **pseudoinverse** solution
- (**unexpected**) collision of a link occurs during the **third** cycle ...





2

Null-space methods

general solution of $J\dot{q} = \dot{r}$

$$\dot{q} = J^\# \dot{r} + (I - J^\# J) \dot{q}_0$$

a particular solution
(here, the pseudoinverse)
in $\mathcal{R}(J^T)$

“orthogonal” projection
of \dot{q}_0 in $\mathcal{N}(J)$

all solutions of the associated
homogeneous equation $J\dot{q} = 0$
(self-motions)

- symmetric
- idempotent: $[I - J^\# J]^2 = [I - J^\# J]$
- $[I - J^\# J]^\# = [I - J^\# J]$
- $J^\# \dot{r}$ is orthogonal to $[I - J^\# J] \dot{q}_0$

properties of
projector $[I - J^\# J]$

even more in general...

$$\dot{q} = K_1 \dot{r} + (I - K_2 J) \dot{q}_0$$

... but with less nice properties!

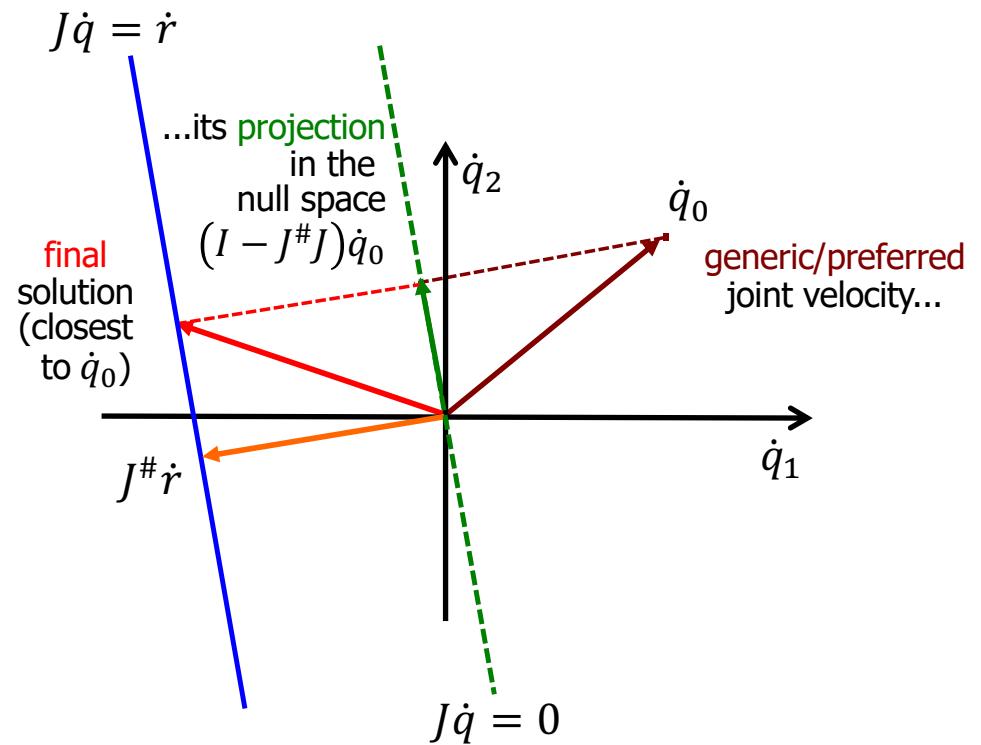
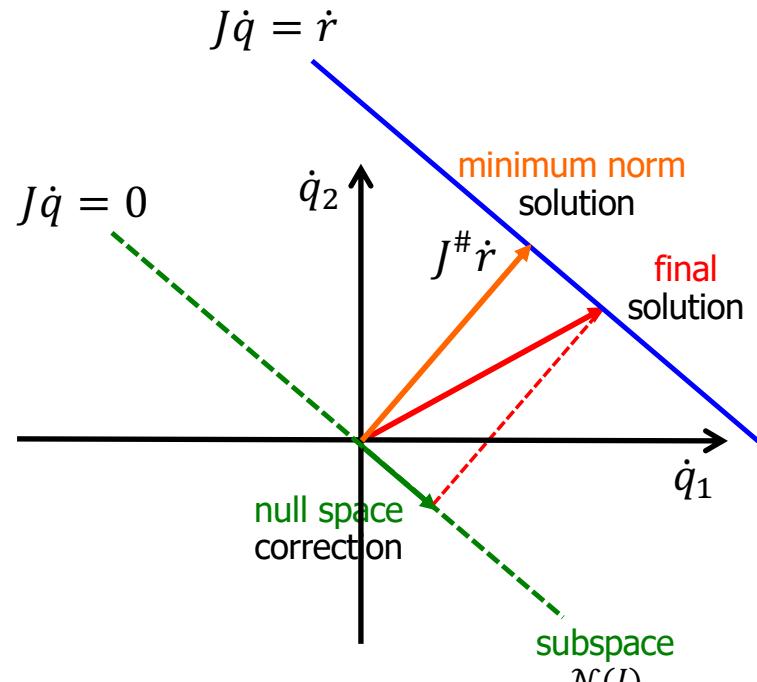
K_1, K_2 generalized
inverses of J
($J K_i J = J$)

how do we choose \dot{q}_0 ?



Geometric view on Jacobian null space

in the space of velocity commands



a correction is added to the original pseudoinverse (minimum norm) solution
 i) which is in the **null space** of the Jacobian
 ii) and possibly satisfies **additional criteria** or objectives



Linear-Quadratic Optimization

generalities

$$\begin{aligned} \min_x H(x) &= \frac{1}{2} (x - x_0)^T W (x - x_0) \\ \text{s.t. } Jx &= y \end{aligned}$$

M × N

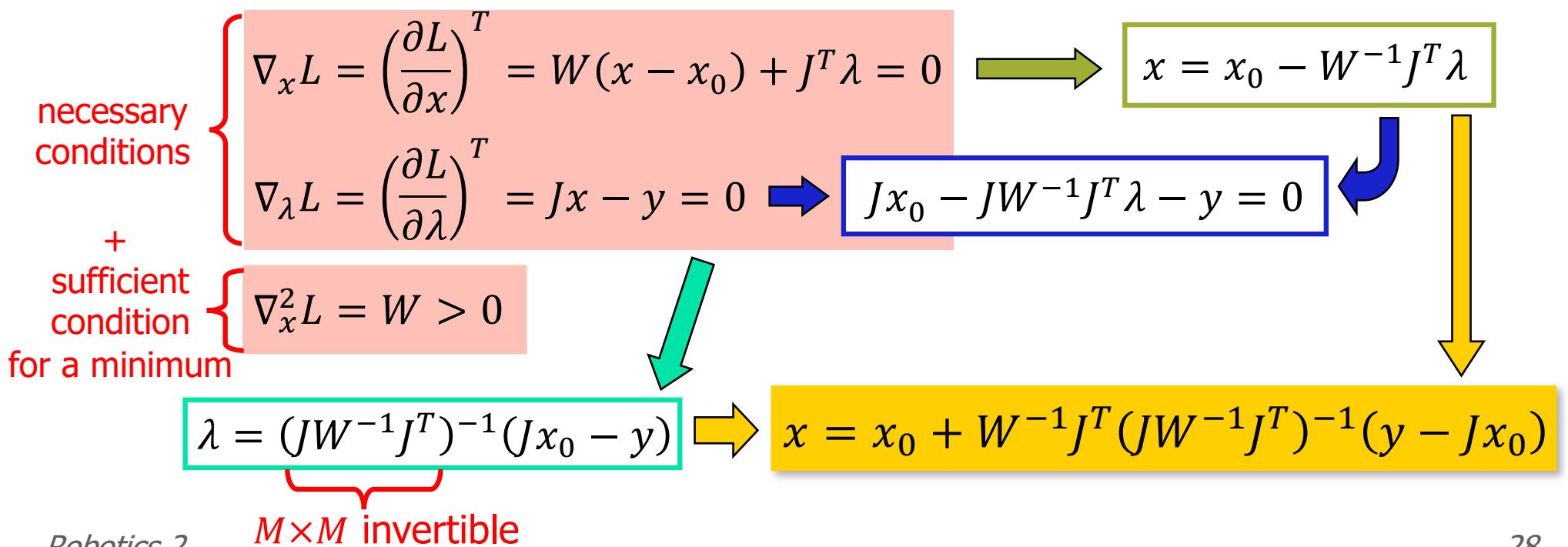
$$x \in \mathbb{R}^N$$

$$W > 0 \text{ (symmetric)}$$

$$y \in \mathbb{R}^M$$

$$\text{rank}(J) = \rho(J) = M$$

$$L(x, \lambda) = H(x) + \lambda^T (Jx - y) \leftarrow \text{Lagrangian (with multipliers } \lambda\text{)}$$





Linear-Quadratic Optimization

application to robot redundancy resolution

PROBLEM

$$\begin{aligned} \min_{\dot{q}} H(\dot{q}) &= \frac{1}{2} (\dot{q} - \dot{q}_0)^T W (\dot{q} - \dot{q}_0) \\ \text{s.t. } J\dot{q} &= \dot{r} \end{aligned}$$

\dot{q}_0 is a
“privileged”
joint velocity

SOLUTION

$$\dot{q} = \dot{q}_0 + W^{-1} J^T (J W^{-1} J^T)^{-1} (\dot{r} - J \dot{q}_0)$$

$$J_W^\#$$

$$\dot{q} = J_W^\# \dot{r} + (I - J_W^\# J) \dot{q}_0$$

minimum weighted norm
solution (for $\dot{q}_0 = 0$)

“projection” matrix in
the null-space $\mathcal{N}(J)$

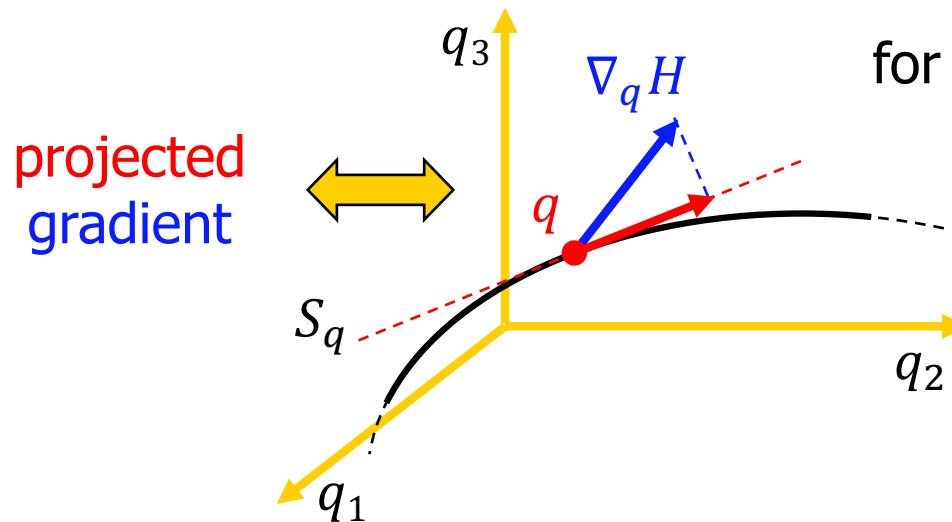


Projected Gradient (PG)

$$\dot{q} = J^\# \dot{r} + (I - J^\# J) \dot{q}_0$$

the choice $\dot{q}_0 = \nabla_q H(q)$ → differentiable objective function
 realizes one step of a constrained optimization algorithm

while executing the time-varying task $r(t)$
 the robot tries to increase the value of $H(q)$



for a fixed \bar{r} : $S_q = \{q \in \mathbb{R}^N : f(q) = \bar{r}\}$

$$\Rightarrow \dot{q} = (I - J^\# J) \nabla_q H$$

$$(I - J^\# J) \nabla_q H = 0$$

N -dimensional
 is a necessary condition
 of constrained optimality



Typical objective functions $H(q)$

- **manipulability** (maximize the “distance” from singularities)

$$H_{\text{man}}(q) = \sqrt{\det[J(q)J^T(q)]}$$

- **joint range** (minimize the “distance” from the mid points of the joint ranges)

$$\begin{aligned} q_i &\in [q_{m,i}, q_{M,i}] \\ \bar{q}_i &= \frac{q_{M,i} + q_{m,i}}{2} \end{aligned}$$

$$H_{\text{range}}(q) = \frac{1}{2N} \sum_{i=1}^N \left(\frac{q_i - \bar{q}_i}{q_{M,i} - q_{m,i}} \right)^2$$

$$\dot{q}_0 = -\nabla_q H(q)$$

- **obstacle avoidance** (maximize the minimum distance to Cartesian obstacles)

also known as
“clearance”

$$H_{\text{obs}}(q) = \min_{\substack{a \in \text{robot} \\ b \in \text{obstacles}}} \|a(q) - b\|^2$$

potential difficulties due
to non-differentiability
(this is a max-min problem)

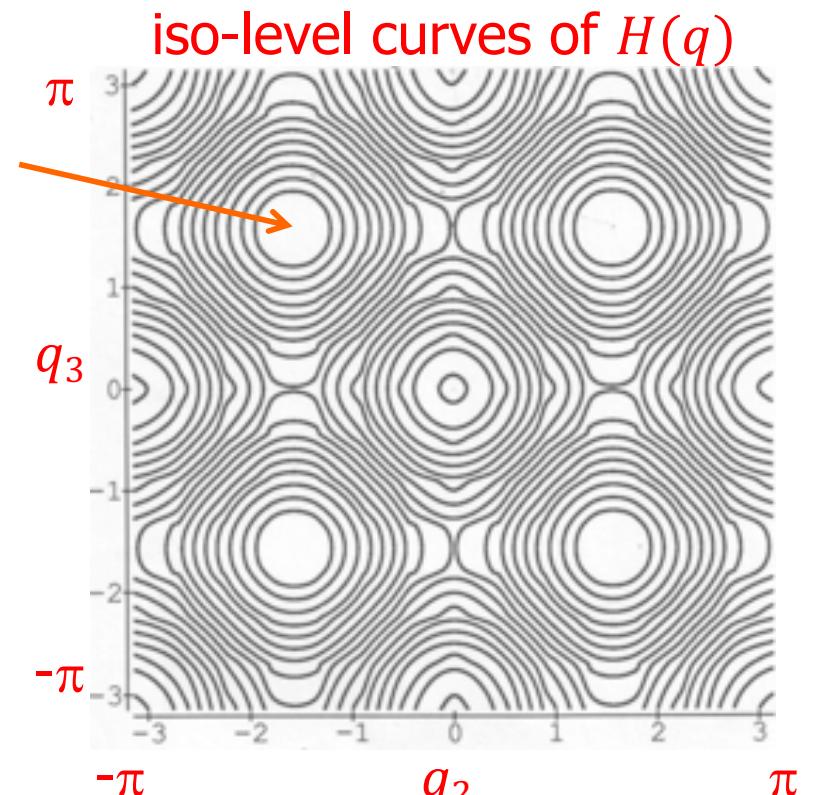
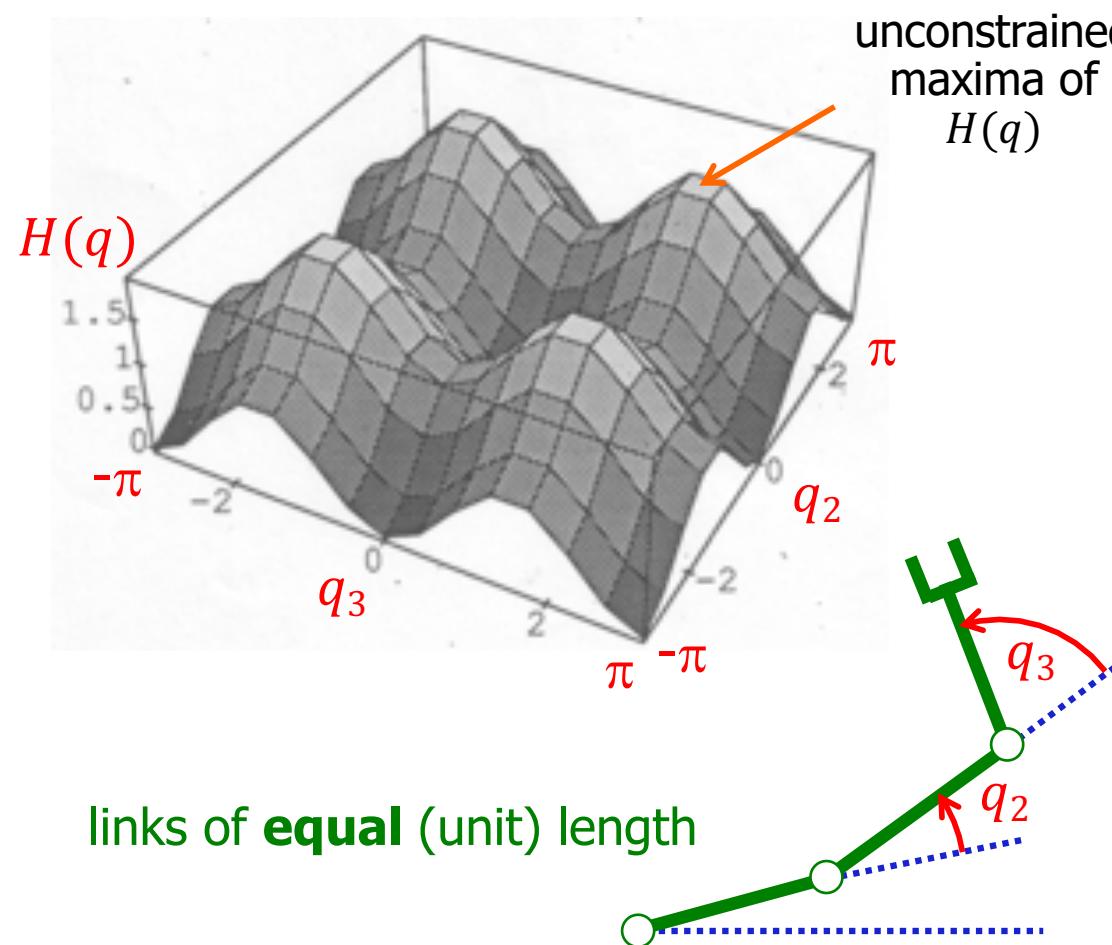


Singularities of planar 3R arm

the robot is redundant
for a positioning task
in the plane ($M = 2$)

$$H(q) = \sin^2 q_2 + \sin^2 q_3$$

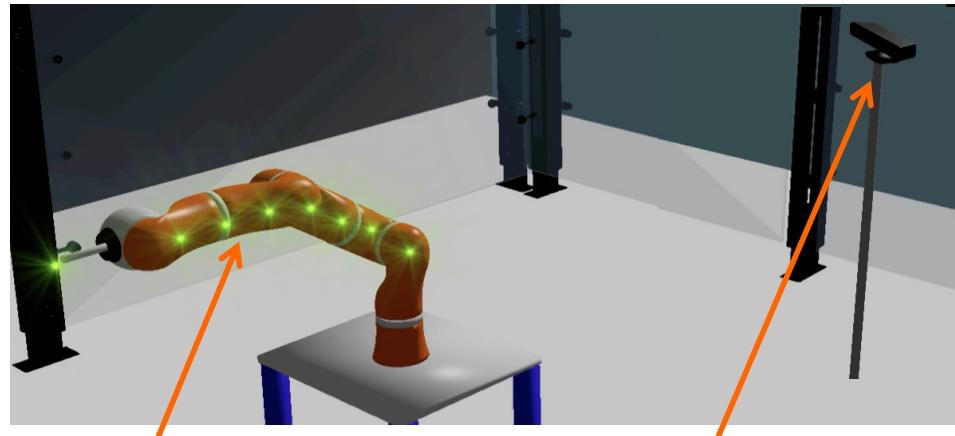
this H is **not** H_{man}
but has the **same** minima



independent from q_1 !



Minimum distance computation in human-robot interaction

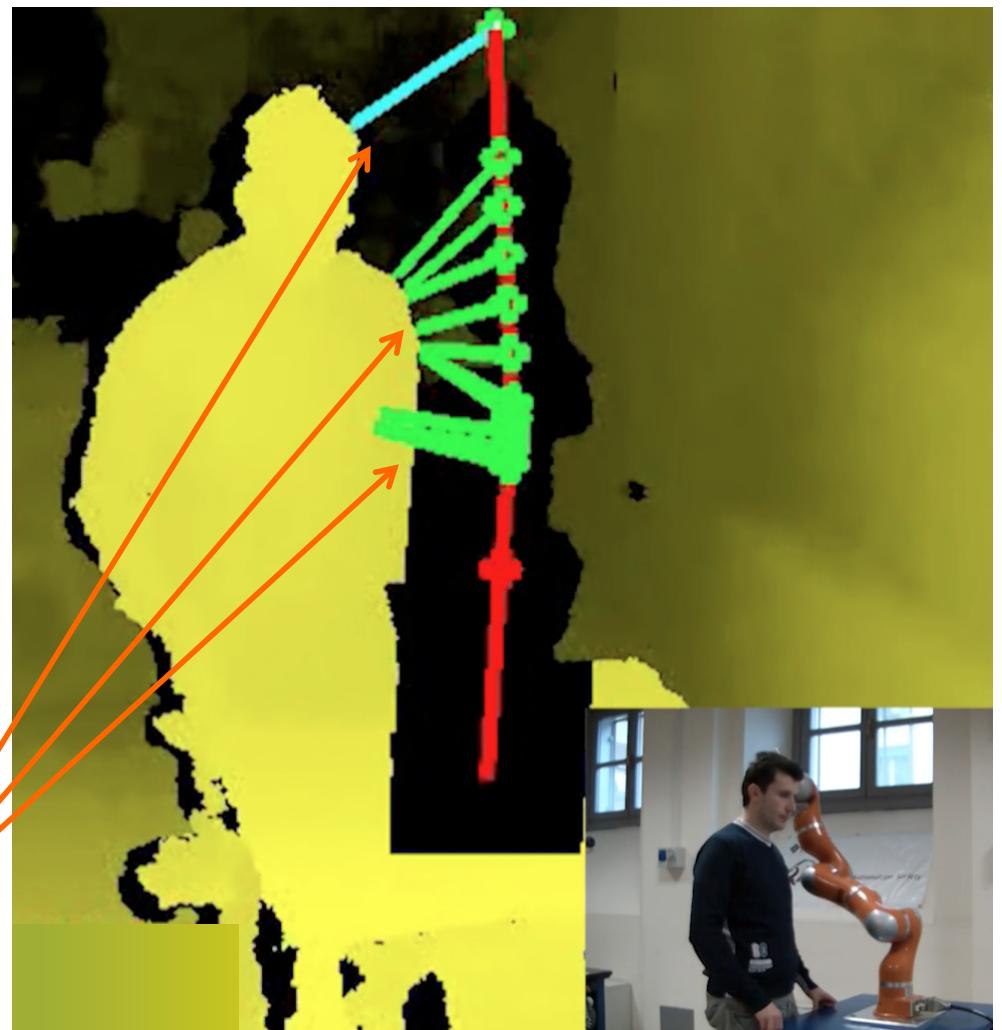


LWR4 robot with
a finite number of
control points $a(q)$
(8, including the E-E)

a Kinect sensor monitors
the workspace giving the
3D position of points b
on obstacles that are
fixed or moving
(like humans)

distances in 3D (and then the clearance)
are computed in this case as

$$\min_{\substack{a \in \{\text{control points}\} \\ b \in \text{human body}}} \|a(q) - b\|^2$$





Comments on null-space methods

- the projection matrix $(I - J^{\#}J)$ has dimension $N \times N$, but only rank $N - M$ (if J is full rank M), with some **waste of information**
- actual (efficient) evaluation of the solution

$$\dot{q} = J^{\#}\dot{r} + (I - J^{\#}J)\dot{q}_0 = \dot{q}_0 + J^{\#}(\dot{r} - J\dot{q}_0)$$

but the pseudoinverse is needed anyway, and this is **computationally intensive** (SVD in the general case)

- in principle, the additional complexity of a redundancy resolution method should depend only on the **redundancy degree $N - M$**
- a constrained optimization method is available, which is known to be more efficient than the projected gradient (PG) —at least when the **Jacobian has full rank ...**



Decomposition of joint space

- if $p(J(q)) = M$, there exists a **decomposition** of the set of joints (possibly, after a reordering)

$$q = \begin{pmatrix} q_a \\ q_b \end{pmatrix} \quad \begin{matrix} M \\ N - M \end{matrix}$$

$\overbrace{}^{M \times M}$

such that $J_a(q) = \frac{\partial f}{\partial q_a}$ is nonsingular

- from the **implicit function theorem**, there exists an inverse function g

$$f(q_a, q_b) = r \quad \rightarrow \quad q_a = g(r, q_b)$$

$$\text{with } \frac{\partial g}{\partial q_b} = - \left(\frac{\partial f}{\partial q_a} \right)^{-1} \frac{\partial f}{\partial q_b} = -J_a^{-1}(q)J_b(q)$$

- the **$N - M$ variables q_b** can be selected **independently** (e.g., they are used for optimizing an objective function $H(q)$, “reduced” via the use of g to a **function of q_b only**)
- $q_a = g(r, q_b)$ is then chosen so as to correctly **execute the task**



Reduced Gradient (RG)

- $H(q) = H(q_a, q_b) = H(g(r, q_b), q_b) = H'(q_b)$, with r at **current** value
- the **Reduced Gradient** (w.r.t. q_b only, but still keeping the effects of this choice into account) is

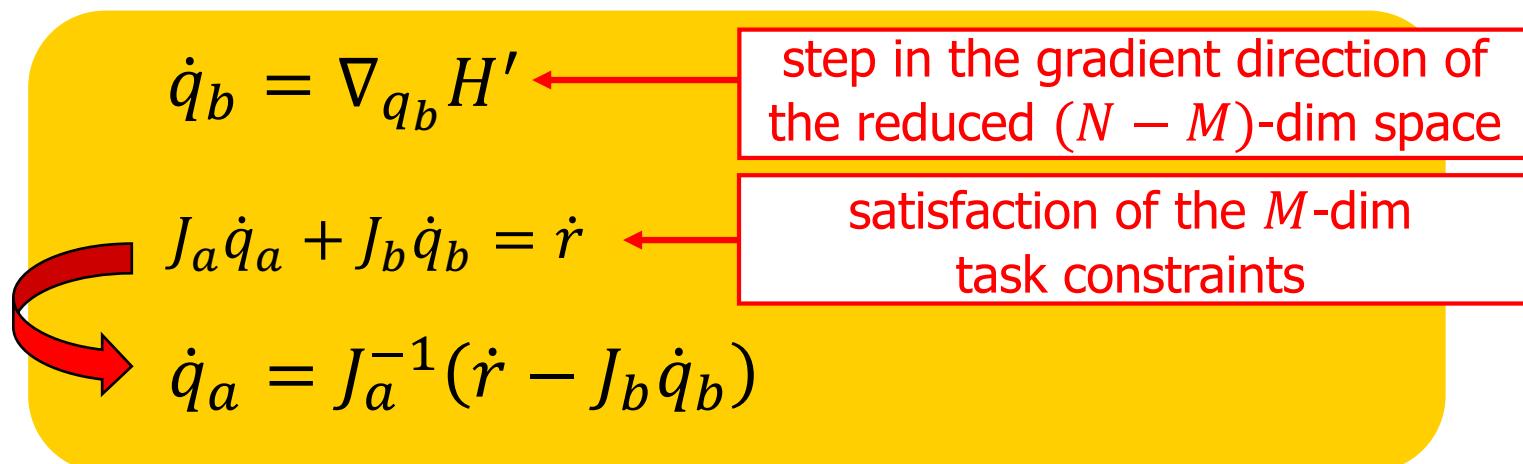
$$\nabla_{q_b} H' = [-(J_a^{-1} J_b)^T \quad I_{N-M}] \nabla_q H$$

$(\neq \nabla_{q_b} H \text{ only}!!)$

$$\nabla_{q_b} H' = 0$$

is a "compact"
(i.e., $N - M$ dimensional)
necessary condition
of constrained optimality

- algorithm





Comparison between PG and RG

- Projected Gradient (PG)

$$\dot{q} = J^{\#}\dot{r} + (I - J^{\#}J)\nabla_q H$$

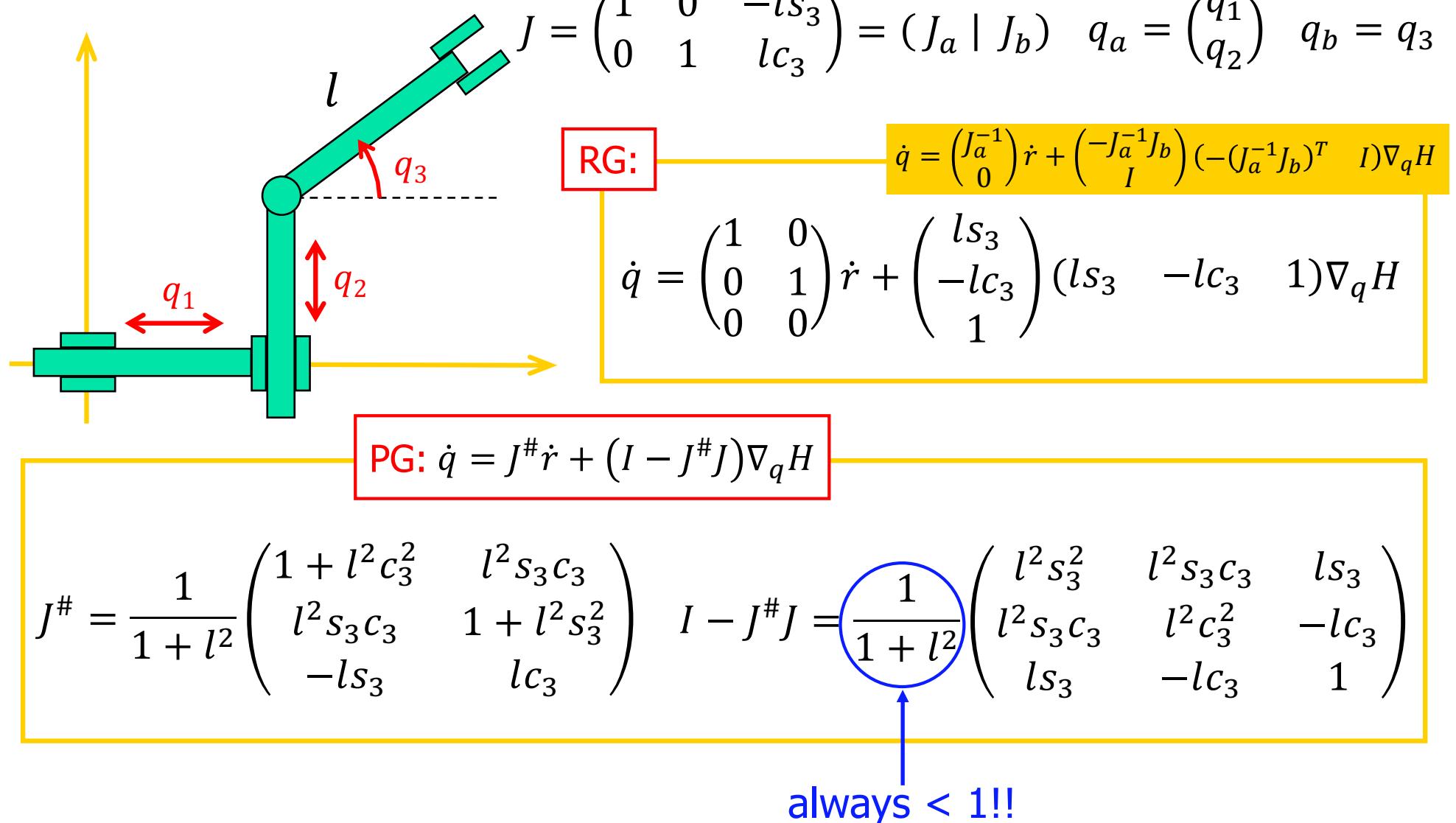
- Reduced Gradient (RG)

$$\dot{q} = \begin{pmatrix} \dot{q}_a \\ \dot{q}_b \end{pmatrix} = \begin{pmatrix} J_a^{-1} \\ 0 \end{pmatrix} \dot{r} + \begin{pmatrix} -J_a^{-1}J_b \\ I \end{pmatrix} (-J_a^{-1}J_b)^T \quad I) \nabla_q H$$

- RG is **analytically** simpler and **numerically** faster than PG, but requires the search for a non-singular minor (J_a) of the robot Jacobian
- if $r = \text{cost}$ & $N - M = 1 \Rightarrow$ same (unique) direction for \dot{q} , but RG has automatically a **larger** optimization step size
- else \Rightarrow RG and PG methods provide always **different evolutions**



Analytic comparison PPR robot





Joint range limits

$$q = \begin{pmatrix} 1 & 0 & 0 & 0 \\ 1 & 1 & 0 & 0 \\ 1 & 1 & 1 & 0 \\ 1 & 1 & 1 & 1 \end{pmatrix} \theta = T\theta$$

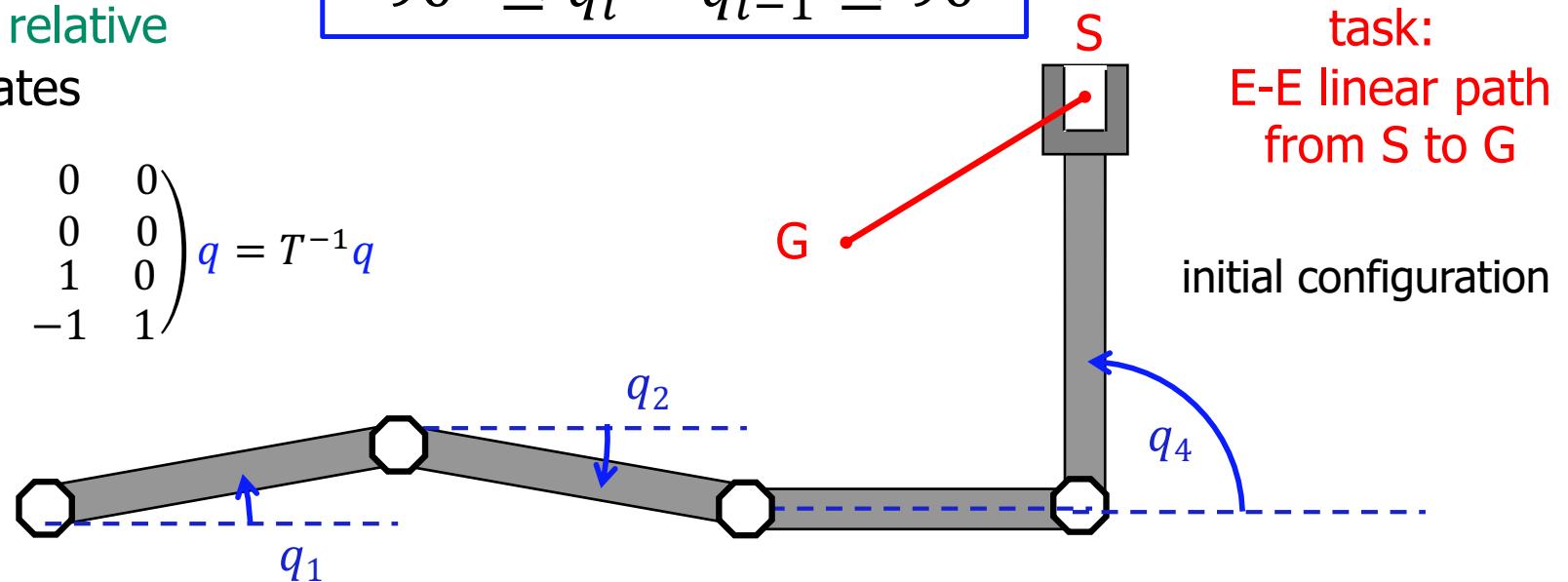
absolute \Leftrightarrow relative
coordinates

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

$$-90^\circ \leq \theta_i \leq 90^\circ$$

\Updownarrow

$$-90^\circ \leq q_i - q_{i-1} \leq 90^\circ$$

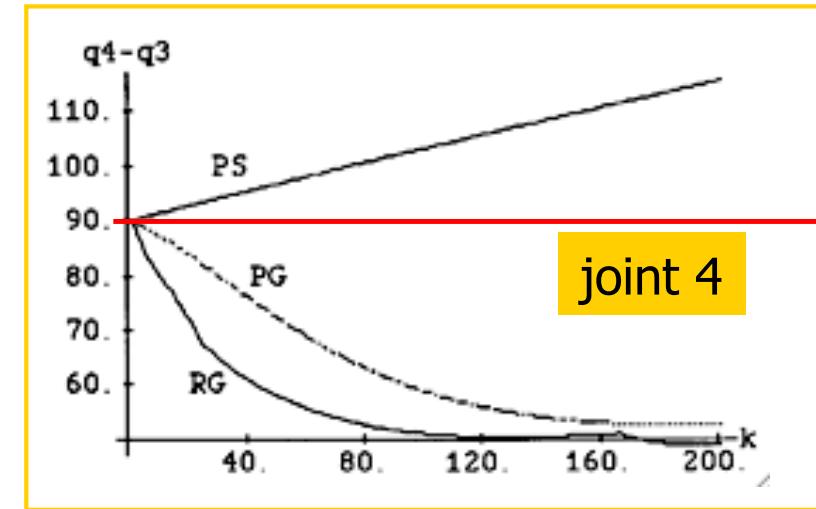
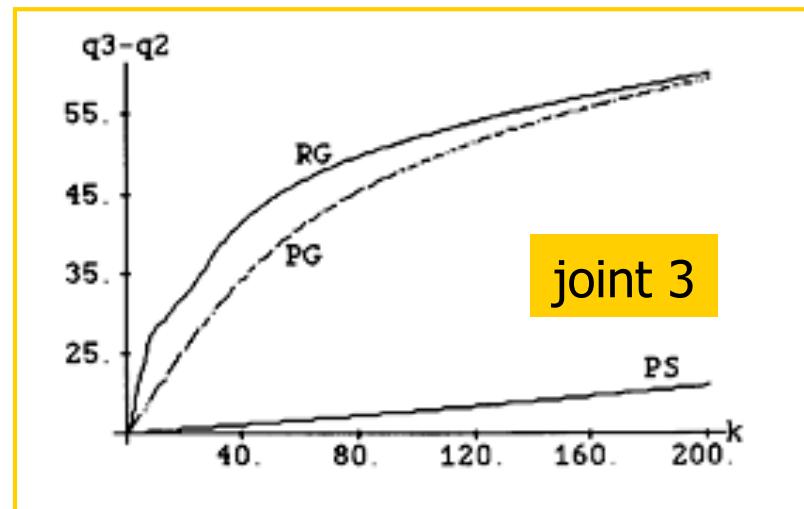
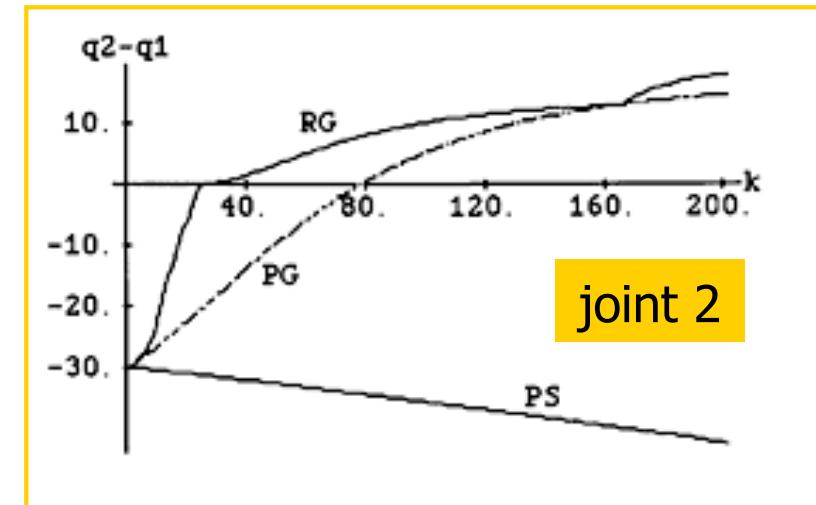
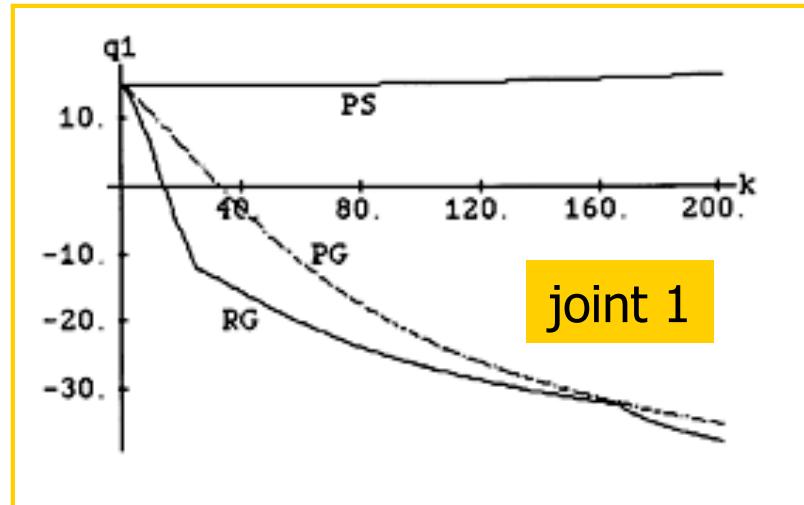


numerical comparison among pseudoinverse (**PS**),
projected gradient (**PG**), and reduced gradient (**RG**) methods



Numerical results

minimizing distance from mid joint range

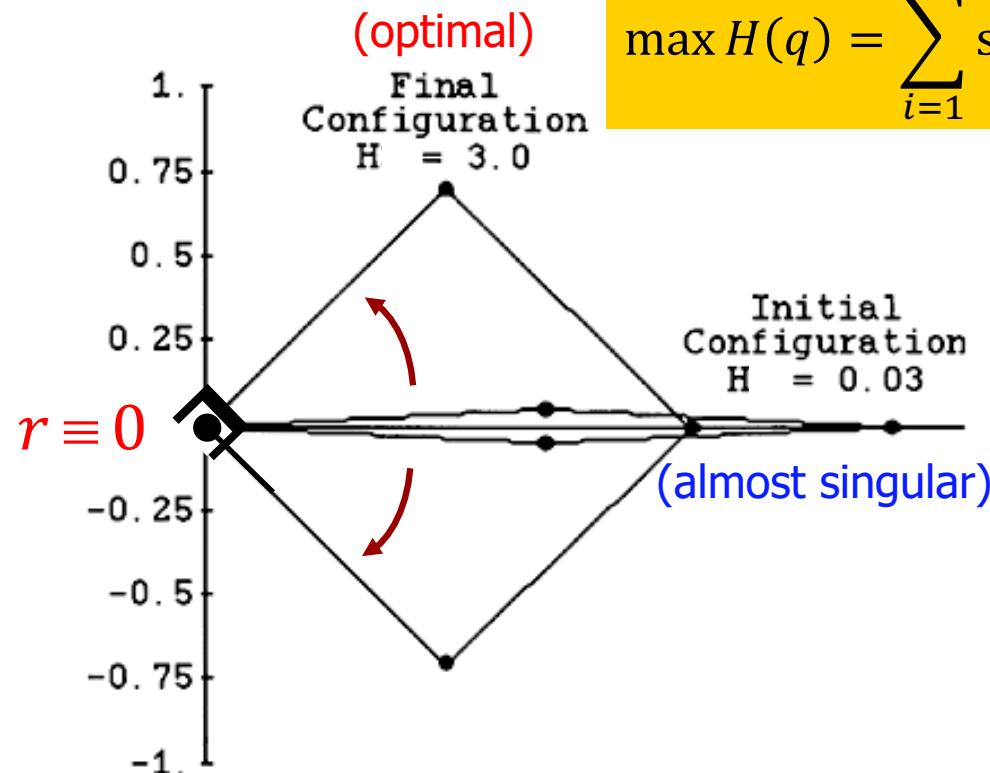


steps of numerical simulation



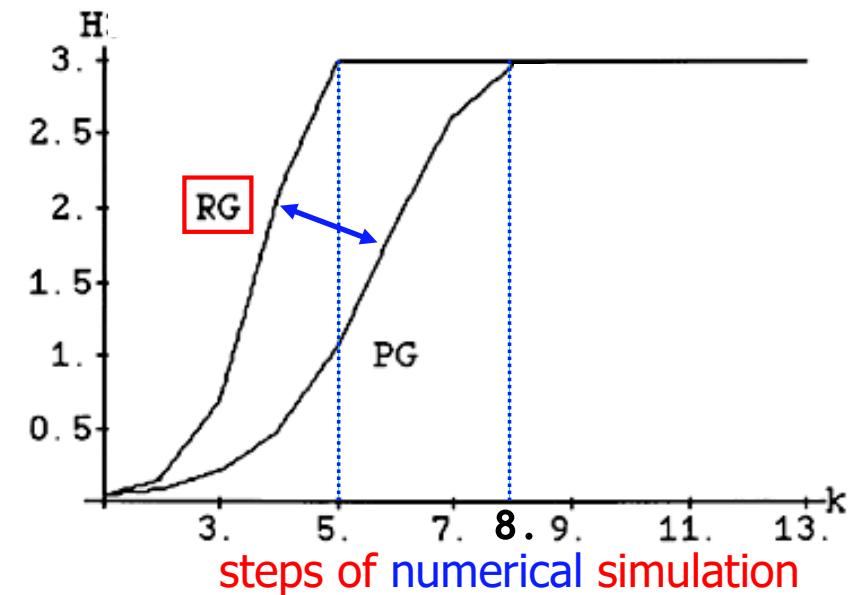
Numerical results

self-motion for escaping singularities



$$\max H(q) = \sum_{i=1}^3 \sin^2(q_{i+1} - q_i)$$

this function is **NOT**
the manipulability index,
but has the same minima ($= 0$)



RG is faster than PG
(keeping the same accuracy on r)



3

Task augmentation methods

- an auxiliary task is added (task augmentation)

$$S \updownarrow f_y(q) = y \quad S \leq N - M$$

corresponding to some desirable feature for the solution

$$r_A = \begin{pmatrix} r \\ y \end{pmatrix} = \begin{pmatrix} f(q) \\ f_y(q) \end{pmatrix} \rightarrow \dot{r}_A = \begin{pmatrix} J(q) \\ J_y(q) \end{pmatrix} \dot{q} = J_A(q) \dot{q}$$

$\boxed{J_A}$ } $M + S$
 N

- a solution is chosen still in the form of a generalized inverse

$$\dot{q} = K_A(q) \dot{r}_A$$

or by adding a term in the null space of the augmented Jacobian matrix J_A



Augmenting the task ...

- **advantage:** better shaping of the inverse kinematic solution
- **disadvantage:** algorithmic singularities are introduced when

$$\rho(J) = M \quad \rho(J_y) = S \quad \text{but} \quad \rho(J_A) < M + S$$

to avoid this, it should be always

$$\mathcal{R}(J^T) \cap \mathcal{R}(J_y^T) = \emptyset$$

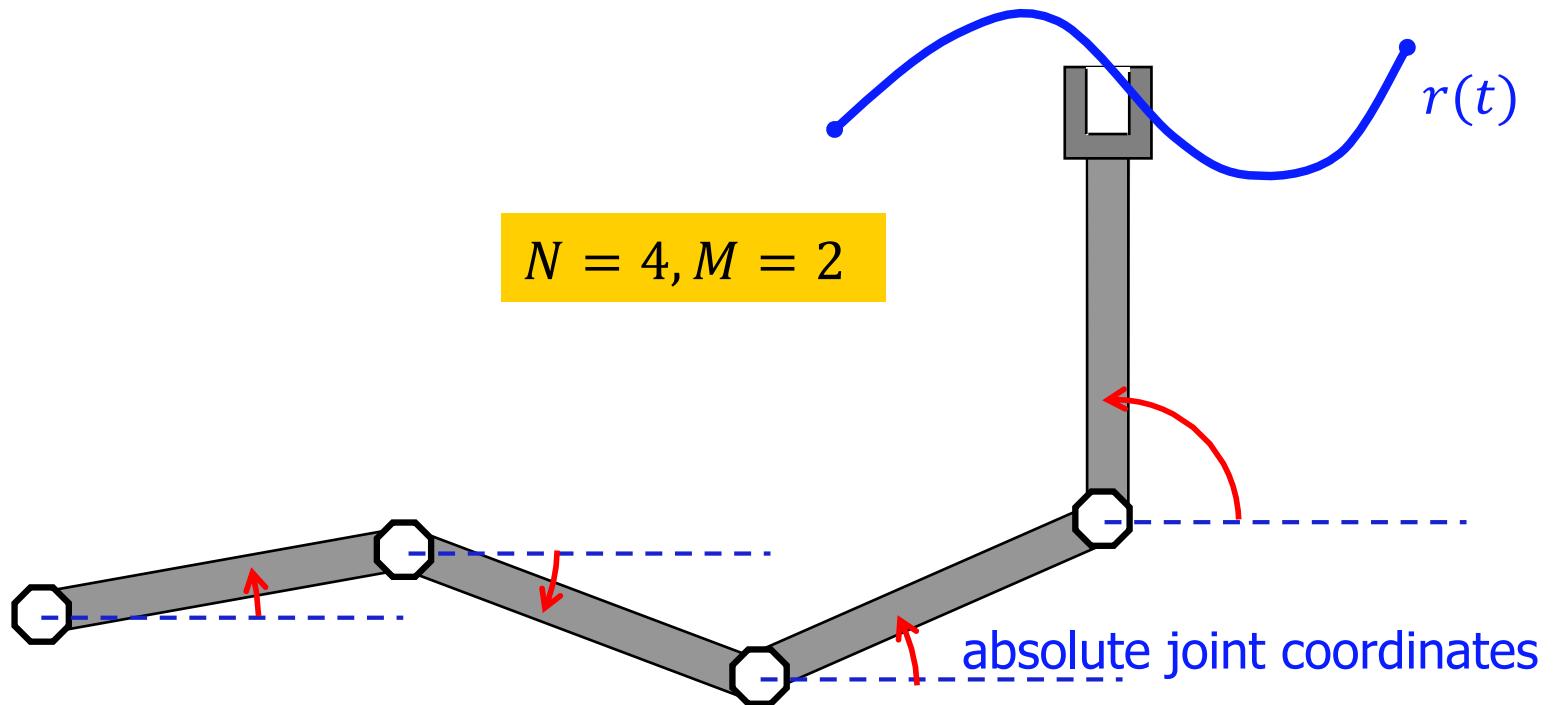
difficult to be obtained globally!

rows of J AND rows of J_y
are all together linearly independent





Augmented task example



$$f_y(q) = q_4 = \pi/2 \quad (S = 1)$$

last link is to be held vertical...



Extended Jacobian ($S = N - M$)

- square J_A : in the absence of **algorithmic** singularities, we can choose

$$\dot{q} = J_A^{-1}(q)\dot{r}_A$$

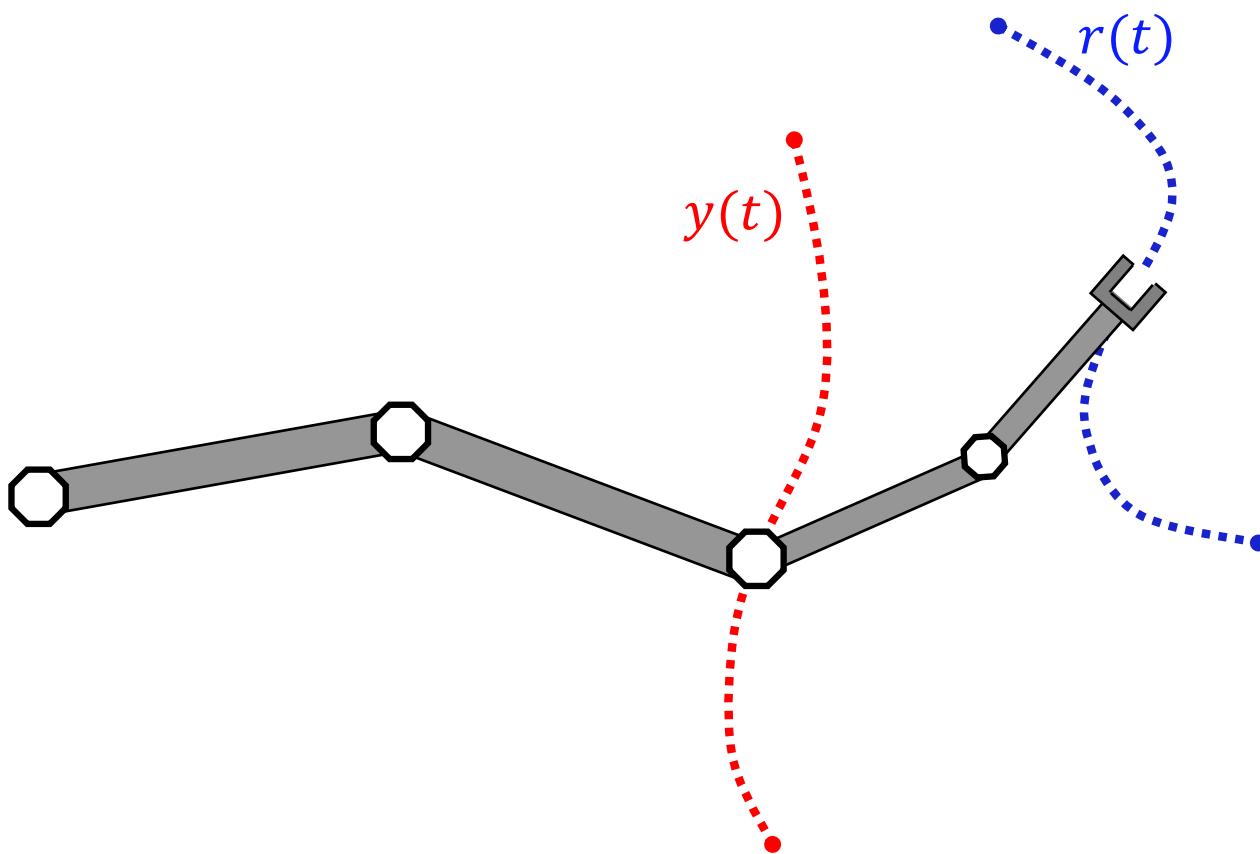
- the scheme is then **repeatable**
 - provided no singularities are encountered during a complete task cycle*
- when the $N - M$ conditions $f_y(q) = 0$ correspond to necessary (and sufficient) conditions for constrained optimality of a given objective function $H(q)$ (see RG method, slide #36), this scheme guarantees that constrained **optimality** is locally **preserved** during task execution
- in the vicinity of algorithmic singularities, the execution of **both** the **original task** as well as the **auxiliary task(s)** are affected by **errors** (when using DLS inversion)

* there exists an unexpected phenomenon in some 3R manipulators having “generic” kinematics: the robot may sometimes perform a pose change after a full cycle, even if no singularity has been encountered during motion (see J. Burdick, *Mech. Mach. Theory*, 30(1), 1995)



Extended Jacobian example

MACRO-MICRO manipulator



$$N = 4, M = 2$$

$$\dot{r} = J(q_1, \dots, q_4)\dot{q}$$
$$\dot{y} = J_y(q_1, q_2)\dot{q}$$



$$J_A = \begin{pmatrix} * & * \\ * & 0 \end{pmatrix} \quad 4 \times 4$$



Task Priority

if the original (primary) task $\dot{r}_1 = J_1(q)\dot{q}$ has **higher priority** than the auxiliary (secondary) task $\dot{r}_2 = J_2(q)\dot{q}$

- we **first** address the task with highest priority

$$\dot{q} = J_1^\# \dot{r}_1 + (I - J_1^\# J_1) v_1$$

- and **then** choose v_1 so as to satisfy, if possible, also the secondary (lower priority) task

$$\dot{r}_2 = J_2 \dot{q} = J_2 J_1^\# \dot{r}_1 + J_2 (I - J_1^\# J_1) v_1 = J_2 J_1^\# \dot{r}_1 + J_2 P_1 v_1$$

the general solution for v_1 takes the usual form

$$v_1 = (J_2 P_1)^\# (\dot{r}_2 - J_2 J_1^\# \dot{r}_1) + (I - (J_2 P_1)^\# (J_2 P_1)) v_2$$

v_2 is available for the execution of further tasks of lower (ordered) priorities



Task Priority (continue)

- substituting the expression of v_1 in \dot{q}

$$\dot{q} = J_1^\# \dot{r}_1 + P_1 (J_2 P_1)^\# (\dot{r}_2 - J_2 J_1^\# \dot{r}_1) + P_1 \left(I - (J_2 P_1)^\# (J_2 P_1) \right) v_2$$

$P(BP)^\# = (BP)^\#$
when matrix P is
idempotent and symmetric

$$= (J_2 P_1)^\#$$

possibly = 0

- main advantage: highest priority task is ideally no longer affected by algorithmic singularities (error is restricted only to secondary task)

