

A Consideration of Inflatable Circles

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1 Introduction

This is a study of the basic math of inflatable spheres as a tool for soft robotics. We begin with a study in two dimension to simplify the problem. Our final goal is to analyze three dimensional soft robots composed of inflatable spheres.

2 Problem I: Circles in Fixed Postions

A very simplified version of the problem is to imagine that a two-dimensional plane. Instead of spheres, we will assume we have circles of changable radius. This is in fact realistic of a soft robot constrained to a plane.

Eventually we hope to have circles pressing against each other, or tangent or “kissing”. However, the problem is a bit simpler if we assume we have two circles, each of which is constrained to have its center on the a vertical line (see Figure 4.) We place the circle C_1 with radius r_1 on the $x = -1$ line, and assume that it rests on a shelf or plane on the x -axis. Assume the C_2 circle whose radius if r_2 is on the $x = 1$ line.

Let A the intersection of the tangent line supported by the inflatable circles with the x -axis. Call the distance of A on the x -axis x . Let ψ be the angle formed by the circle centers with the x axis (measured counterclockwise).

If the radii are less than 1 so that no issues of intersection of the circles arise, we have:

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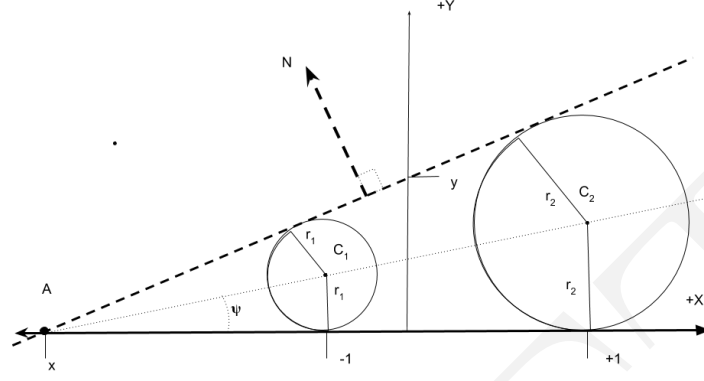


Figure 1: Problem I: Fixed Circles Centers

$$\tan \psi = \frac{r_1}{x-1} = \frac{r_2}{x+1} \quad (1)$$

$$r_2(x-1) = r_1(x+1) \quad (2)$$

$$r_2x - r_2 = r_1x + r_1 \quad (3)$$

$$r_2x - r_1x = r_1 + r_2 \quad (4)$$

$$x(r_2 - r_1) = r_1 + r_2 \quad (5)$$

$$x = \frac{r_1 + r_2}{r_2 - r_1} \quad (6)$$

$$\tan \psi = \frac{r_1}{x-1} \quad (7)$$

$$\psi = \arctan \frac{r_1}{x-1} \quad (8)$$

$$N = \begin{bmatrix} -\sin \psi \\ \cos \psi \end{bmatrix} \quad (9)$$

$$(10)$$

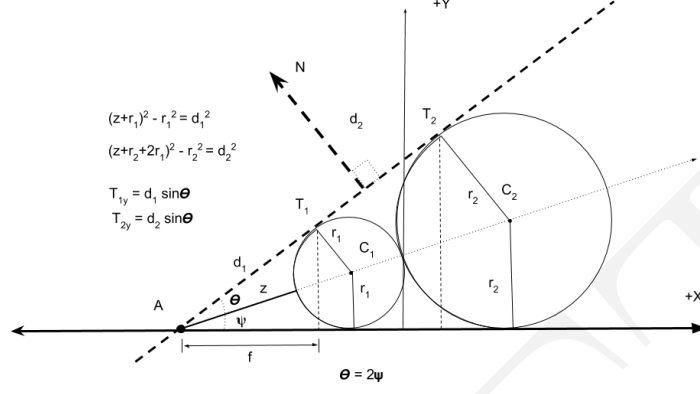


Figure 2: Problem II: Tangent Circles

3 Problem II: Tangent Circles

$$\frac{r_2}{\|(C_2 - A)\|} = \frac{r_1}{\|(C_1 - A)\|} \quad (11)$$

$$\|C_2 - A\| = r_2 + 2r_1 + z \quad (12)$$

$$\|C_1 - A\| = r_1 + z \quad (13)$$

$$\frac{r_2}{r_2 + 2r_1 + z} = \frac{r_1}{r_1 + z} \quad (14)$$

$$z = -\frac{2r_1^2}{r_1 - r_2} \text{ and } r_1 \neq r_2 \text{ and } r_1 r_2 (r_1 + r_2) \neq 0 \quad (15)$$

$$\sin \psi = \frac{r_1}{z + r_1} \quad (16)$$

$$\sin \psi = \frac{r_1}{z + r_1} \quad (17)$$

$$\theta = 2 \arcsin \frac{r_1}{z + r_1} \quad (18)$$

$$N_x = -\sin \pi/2 + \theta \quad (19)$$

$$N_y = -\cos \pi/2 + \theta \quad (20)$$

$$(21)$$

We would like to know the coordinates of T_1 and T_2 .

$$d_1 = \sqrt{(z + r_1)^2 - r_1^2} \quad (22)$$

$$d_2 = \sqrt{(z + r_2 + 2r_1)^2 - r_2^2} \quad (23)$$

$$T_{1y} = d_1 \sin \theta \quad (24)$$

$$T_{2y} = d_2 \sin \theta \quad (25)$$

$$A_x = (z + 2r_1) \cos \psi \quad (26)$$

$$f = \sqrt{d_1^2 - T_{1y}^2} \quad (27)$$

$$T_{1x} = A_x - f \quad (28)$$

$$T_{2x} = \sqrt{d_2^2 - T_{2y}^2} - A_x \quad (29)$$

$$(30)$$

The slope of the vector $\overrightarrow{T_1 T_2}$ is $\tan \theta$.

$$\overrightarrow{T_1 T_{2x}} = \cos \theta \quad (31)$$

$$\overrightarrow{T_1 T_{2y}} = \sin \theta \quad (32)$$

4 Problem III: Support points of Two tangent spheres

In attempting to solve a latter problem, we identified the following problem as useful.

Suppose that you have two spheres which are tangent. The centers of these spheres are in the XY -plane, in arbitrary positions. Find the three-dimensional coordinates of the “support points”, which are the points upon which a flat plane would rest if lowered onto the spheres. If the spheres are different sizes, these will not quite be the tops of the spheres. Assume the plane is symmetric about the support line; that is, not tilted to one side.

5 Problem: Three Touching Circles

Our goal is to be able to determine the orientation of plane resting on top of three spheres of different radii which are touching each other. Because there is a plane through any three points and we have three spheres, we can construct the plane through the center of these points. The projection of the edges of the spheres onto this plane form three touching circles. Knowing the position of these circles is a valuable prelude to solving the three dimensional problem.

To solve this problem most conveniently, we place the first circle on the negative x -axis, and the second circle on the positive x -axis, with the circles

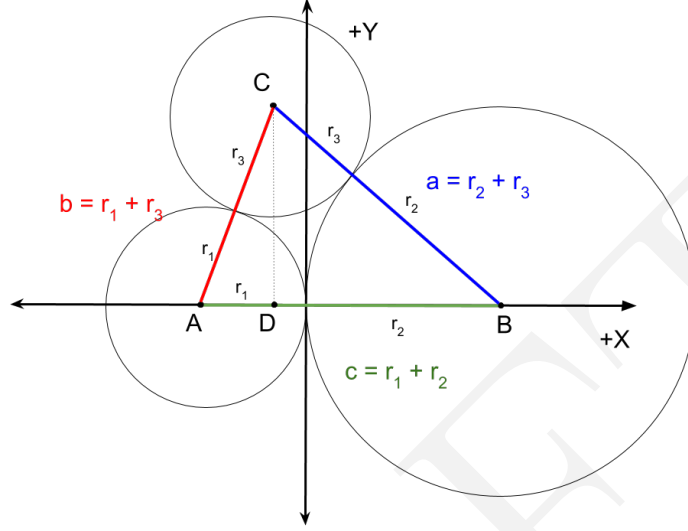


Figure 3: Three Touching Circles

intersecting at the origin. The third circle is placed in the positive y direction. Its center will not be on the y -axis itself unless the radii of the first two circles are equal.

We seek a formula for the coordinates of the third circle in terms of three input radii r_1, r_2, r_3 .

Because the distance between adjacent circles is the sum of their radii, define:

$$a = r_2 + r_3 \quad (33)$$

$$b = r_1 + r_3 \quad (34)$$

$$c = r_1 + r_2 \quad (35)$$

Then we can use the cosine law to compute the angle $\angle ABC = \theta$:

$$\theta = \arccos \frac{a^2 + b^2 - c^2}{2bc} \quad (36)$$

$$\theta = \arccos \frac{(r_2 + r_3)^2 + (r_1 + r_3)^2 - (r_1 + r_2)^2}{2(r_2 + r_3)(r_1 + r_3)} \quad (37)$$

$$(38)$$

It is clear that once θ has been calculated:

$$C_y = a \sin \theta \quad (39)$$

Allowing us to form a right triangle $\triangle ACD$ and use the Pythagorean theorem:

$$b^2 = C_y^2 + (r_1 - C_x)^2 \quad (40)$$

$$b^2 - C_y^2 = (r_1 - C_x)^2 \quad (41)$$

$$\sqrt{b^2 - C_y^2} = r_1 - C_x \quad (42)$$

$$C_x = r_1 - \sqrt{b^2 - C_y^2} \quad (43)$$

6 A progression of Problems

Because we now believe we can model the main problem as the rotation of a plane tangent to a cone about the cone, there are a number of easier problems which may lead us to a solution:

1. In 2D, rotate a tangentially line to a circle until it is coincident on an outside point. That is, given the center of a circle C , a radius r , another point p , what angular rotation (measured against x -axis) gives the rotation that makes a line tangent to C touch p ?
2. Given two spheres, what is the equation for the cone tangent to both?
3. Is the problem better thought of as the intersection of several spheres?

7 Three Touching Spheres

Our fundamental goal now is to describe three touching spheres. As robotocists, our interest is in the slope of the plane of the tops of these spheres as if they were resting on a table. Then by inflating or deflating spheres, we would be able to control the direction of a plane or platform. Such a device is sometimes called a parallel manipulator, of which a Stewart Platform[?] (https://en.wikipedia.org/w/index.php?title=Stewart_platform&oldid=898429010) is the best-known example.

The fundamental action of a parallel manipulator is to tilt a plane or platform in a desired direction. Having developed the math for the three touching circles in the previous section, we now use it to find the normal of the a plane resting on the top of three spheres by choosing our coordinate system to the plane defined by the center points of the three spheres. In this coordinate system, the z -coordinate of the center of all spheres is 0. The projection of all three spheres into this plane produces three touching circles. We seek an expression for the normal of the plane of the tops of these spheres as a function purely of the three radii. Call this plane the *top* plane.

As the top plane tilts, the points tangent to this plane move away from the highest points on each of the three spheres, making the problem more difficult.

This problem can clearly be solved quickly using numerical methods, because by guessing a candidate normal to the top plane, it is relatively easy to compute

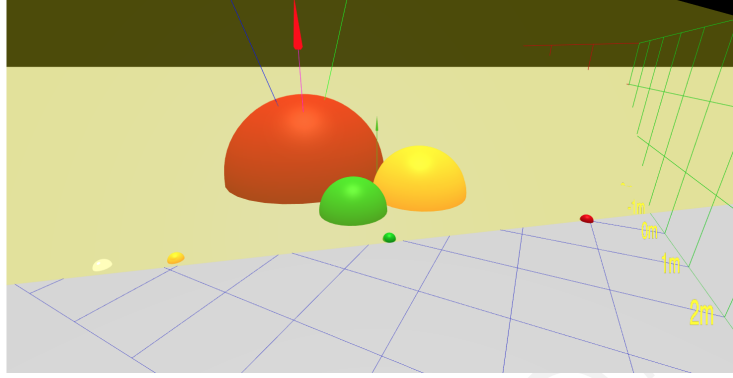


Figure 4: Three Touching Spheres

an error function based on the distance between the closest point on each sphere to the top plane and the top plane. We would expect an iterative approach to converge very quickly.

Nonetheless we seek an analytic solution.

7.1 Variable definitions

We assume that the spheres centered at points A, B , and C of radii r_A, r_b , and r_c . We setup our coordinate system as a right-handed coordinate system with XZ plane containing the center of all spheres. The A sphere is placed at the origin, so that $O = A$, and the B sphere is placed on the positive X axis. Without loss of generality assume $r_a \geq r_b \geq r_c$. Following computer graphics convention, we think of the Y dimension as vertical.

Taking any two spheres defines a cone whose apex is in the XZ plane. Call the apex of the AB cone U , the AC cone V , and the BC cone W .

We assert that these three points form a line, which we call the *apex line*, in the XZ plane and that this line is the intersection of the *tangent plane* touching all three spheres at a single point with the XZ plane. We will use points U and V in our calculation. Let α be the half-angle of the AB cone.

It behooves us to name the intersection of the apex line with the Z axis, I_z , so that we can use it in calculations.

7.2 Strategy

We seek to compute the normal of the tangent plane. Observe that this plane is tangent to all three cones. Observe that the AB cone intersects the A sphere in a circle on the surface of the A perpendicular to and centered on the X axis.

A vector of length r_A that begins pointing in the X direction and is rotated counterclockwise about the Z -axis by $\pi/2 - \alpha$.

However, we must rotate this vector about the X axis by an unknown amount θ in order to bring capture the tilt which is not purely a rotation about the Z

axis. Since this angle is computed in the ZY plane, we compute a projection of the point V into that plane, forming a triangle in the ZY plane. Call this point I_z , the intersection of the apex line with the Z -axis.

8 Thing to Research

Idea: It may be possible to solve for the support points as the intersection of cones[?].