

Differential Drive Mobile Robot

December 15, 2022

1 Modelling

In this section, the dynamic modelling of the robot is described. The material is derived from this paper [1]. The robot configuration is depicted in Following figure:

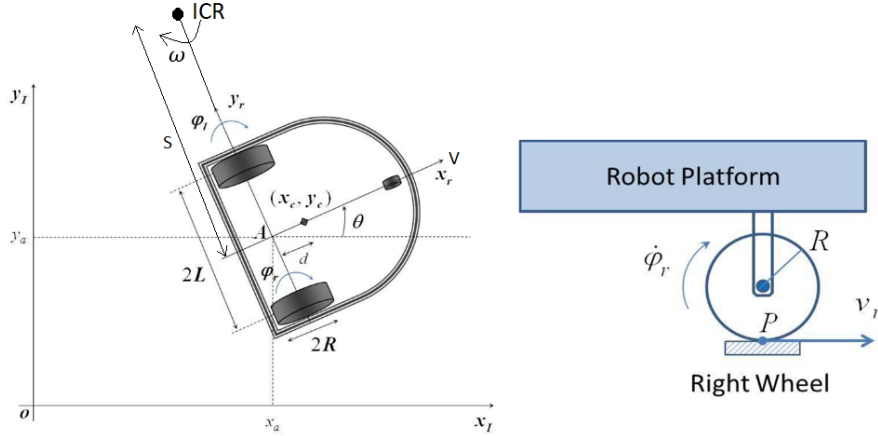


Figure 1: Caption

where $\{X_I, Y_I\}$ is the global frame fixed in the environment (inertial frame), $\{X_r, Y_r\}$ the frame attached to the robot (robot frame), $q^I = \begin{bmatrix} x_a \\ y_a \\ \theta \end{bmatrix}$ robot pose in the inertial frame. The pose of any point in the robot frame ($X^r = \begin{bmatrix} x^r \\ y^r \\ \theta^r \end{bmatrix}$)

and the inertial frame ($X^I = \begin{bmatrix} x^I \\ y^I \\ \theta^I \end{bmatrix}$) are related as

$$\begin{aligned} X^I &= R(\theta)X^r = \begin{bmatrix} \cos\theta & -\sin\theta & 0 \\ \sin\theta & \cos\theta & 0 \\ 0 & 0 & 1 \end{bmatrix} \\ \dot{X}^I &= R(\theta)\dot{X}^r \end{aligned} \quad (1)$$

1.1 Kinematic Model

The motion of the robot is characterized by the following two non-holonomic constraints:

- No lateral slip: The robot only moves forward and backward not sideward:

$$\dot{y}_a^r = 0 \rightarrow -\dot{x}_a^I \sin\theta + \dot{y}_a^I \cos\theta = 0 \quad (2)$$

- Pure rolling constraint: Each wheel has one contact with the ground (no slipping or skidding). Therefore, the robot always rotates around a point referred as instantaneous center of rotation (ICR) by the angular velocity ω :

$$\begin{aligned} \omega(S + L) &= v_r \\ \omega(S - L) &= v_l \end{aligned} \quad (3)$$

Solving Eq. 3 for ω and S :

$$\begin{aligned} \omega &= (v_r - v_l)/2L \\ S &= L \frac{v_r + v_l}{v_r - v_l} \end{aligned} \quad (4)$$

Therefore the velocity of the robot is

$$V = \omega S = \frac{v_r + v_l}{2} \quad (5)$$

By combining Equations 4, 5, and 2, the robot pose in the robot frame is

$$\begin{bmatrix} \dot{x}_a^r \\ \dot{y}_a^r \\ \dot{\theta} \end{bmatrix} = \begin{bmatrix} \frac{R}{2} & \frac{R}{2} \\ 0 & 0 \\ \frac{R}{2L} & -\frac{R}{2L} \end{bmatrix} \begin{bmatrix} \dot{\phi}_r \\ \dot{\phi}_l \end{bmatrix} \quad (6)$$

The robot pose in the inertial frame is

$$\begin{bmatrix} \dot{x}_a^I \\ \dot{y}_a^I \\ \dot{\theta} \end{bmatrix} = \begin{bmatrix} \frac{R}{2} \cos\theta & \frac{R}{2} \cos\theta \\ \frac{R}{2} \sin\theta & \frac{R}{2} \sin\theta \\ \frac{R}{2L} & -\frac{R}{2L} \end{bmatrix} \begin{bmatrix} \dot{\phi}_r \\ \dot{\phi}_l \end{bmatrix} \quad (7)$$

1.2 Dynamic Model

There are three main approaches for modelling the dynamics of a robot: Lagrangian, Newton-Euler, and Kane's method. In this project, we utilize Lagrangian method to find the model. The generalized coordinates are selected as

$$q = \begin{bmatrix} x_a \\ y_a \\ \theta \\ \phi_r \\ \phi_l \end{bmatrix} \quad (8)$$

The kinetic energy of the robot is

$$\begin{aligned} T &= T_c + T_{wr} + T_{wl} = \\ &\frac{1}{2}m_c v_c^2 + \frac{1}{2}I_c \dot{\theta}^2 + \frac{1}{2}m_w v_r^2 + \frac{1}{2}I_m \dot{\theta}^2 + \frac{1}{2}I_w \dot{\phi}_r^2 + \frac{1}{2}m_w v_l^2 + \frac{1}{2}I_m \dot{\theta}^2 + \frac{1}{2}I_w \dot{\phi}_l^2 \\ T &= \frac{1}{2}m(\dot{x}_a^2 + \dot{y}_a^2) - m_c d \dot{\theta} (\dot{y}_a \cos \theta - \dot{x}_a \sin \theta) + \frac{1}{2}I_w (\dot{\phi}_r^2 + \dot{\phi}_l^2) + \frac{1}{2}I \dot{\theta}^2 \\ m &= m_c + 2m_w \\ I &= I_c + m_c d^2 + 2m_w L^2 + 2I_m \end{aligned} \quad (9)$$

where m_c and I_c are the robot's mass without wheels and moment of inertia about the vertical axis through the CoM, m_w and I_w are the mass of each wheel and the moment of inertia about the wheel axis, and I_m is the wheel's moment of inertia about the wheel diameter. The dynamics of the system is

$$\begin{aligned} M(q)\dot{\eta} + C(q, \dot{q})\eta &= B(q)\tau \\ M(q) &= \begin{bmatrix} I_w + \frac{R^2}{4L^2}(mL^2 + I) & \frac{R^2}{4L^2}(mL^2 - I) \\ \frac{R^2}{4L^2}(mL^2 - I) & I_w + \frac{R^2}{4L^2}(mL^2 + I) \end{bmatrix} \\ C(q, \dot{q}) &= \begin{bmatrix} 0 & \frac{R^2}{2L}m_c d \dot{\theta} \\ -\frac{R^2}{2L}m_c d \dot{\theta} & 0 \end{bmatrix} \\ B(q) &= \begin{bmatrix} 1 & 0 \\ 0 & 1 \end{bmatrix} \end{aligned} \quad (10)$$

where $\eta = \begin{bmatrix} \phi_r \\ \phi_l \end{bmatrix}$ and $\tau = \begin{bmatrix} \tau_r \\ \tau_l \end{bmatrix}$.

References

- [1] R. Dhaouadi and A. A. Hatab, "Dynamic modelling of differential-drive mobile robots using lagrange and newton-euler methodologies: A unified framework," *Advances in Robotics & Automation*, vol. 2, no. 2, pp. 1–7, 2013.