.

Inverse Kinematics in Computer Graphics using FABRIK

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Course: Computer Graphics 2

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April 13th, 2019

Animation is a very important topic in Computer Graphics for the development of video games, simulations and even movies. There has been a lot of research to make it more manageable, easy and accurate. There exist a lot of techniques involving animation. In this paper and its corresponding implementation, one of those is explored.

Before starting with main topic, it is important to understand the topics of **Forward Kinematics** and **Inverse Kinematics**. Let’s say we want to animate a robotic arm to grab a glass of water. To accomplish this task, we can simply hard code the angle values of each part of the arm until we get a decent animation; easy but a lot of work. This process is called ***Forward Kinematics***. If the glass of water is moving around, it is very hard to hard-code the angles. That is where using **Inverse Kinematics** can be used. The concept is, give it the goal position and calculate all the angle from the last joint to the root. This helps a lot with accuracy and constant movement of goal position, and it is well used in other areas like robotics and medicine.

The problem for this Inverse Kinematics is that it is very hard to implement an algorithm to satisfy every problem like dealing with complex figures with a large number of joints and degrees of freedom (Aristidou, 2011). There exist a lot of methods to approach this problem, the most popular is using something called “the Jacobian inverse technique”. But there exists another simpler and effective method called **“Forward and Backward Reaching Inverse Kinematics” (FABRIK)**

FABRIK method involves both and inverse and forward kinematics. A hierarchy of the joints is used to facilitate iteration between parent-child joint angles. First, it is needed to check whether the goal position can be reached or not, given the limits of the joints. If the goal can be reached, the algorithm iterates first through all the joints applying inverse kinematics from last joint (also called the end-effector) to the root, using the goal position. After all calculation is done, the original position would be moved, which is something not desirable, therefore, to fix that, forward kinematics is applied from the first joint (using the original position as goal). This process will be repeated until the end-effector is within an area very close to the goal position, this can be a constant (also called error) that can be set depending of how accurate we want the result. It is important to say that the final result is always an approximation, so this may not work if we require an exact calculation; the iteration could go forever, that is why a depth limit is also needed.

To have more realistic accuracy, there can be added orientation constraints, which are the limits of rotations. This can be used for example when designing a human-like character and limit more than 180 degrees of rotation, which is not natural.

In the code provided, there are two implementations, a simple arm reaching a point and a better version of the running robot from the first assignment using FABRIK. There are some glitches because of the rotation matrices, but the algorithms work well enough.

In conclusion, FABRIK is an effective and easy approach to do animation, with only providing the goal position, all the angles can be calculated to reach that desired point.

**References**

Aristidou, A., Lasenby, J. (2011). FABRIK: A fast, iterative solver for the Inverse Kinematics problem. *Graphical Models, 73,* 243-260.