Validation of the Resetability (R) Concept Across Domains

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This document consolidates simulation data across multiple dynamic environments to evaluate the Resetability (R) metric. The R value measures rotational reversibility on SO(3), providing a quantitative way to assess how efficiently a system can return to its nominal attitude after complex rotational disturbances.

1. Methodology

Four experimental domains were used for empirical validation:

- Gravity-bound robot simulations using PyBullet (robot_reset_pybullet.py)
- Zero-gravity floating robot simulations (robot_reset_free.py)
- Spacecraft attitude reset simulations (spacecraft_reset_demo.py)
- Booster Monte Carlo attitude stabilization runs (booster_reset_demo.py)

Each experiment generated a structured CSV file in the results directory, containing Resetability (R), residual attitude error, and recovery time (t_recover) metrics. The present validation script automatically aggregates these files and computes Pearson correlations between R, residual error, and recovery time for each domain.

2. Correlation Summary

Domain	Corr(R,Residual)	Corr(R,RecoveryTime)
booster	0.3187	0.0000
gravity	0.5475	0.0000
spacecraft	-0.3633	0.0551
zeroG	0.1334	0.7640

These values were computed using Pearson correlation coefficients between Resetability (R) and the measured metrics across each simulation domain.

3. Results Overview

The following figures (generated automatically during the validation process) summarize the relationships between Resetability (R) and both residual orientation error and recovery time across all tested domains.

[Figure 1: Residual vs Resetability (R)]

(Image missing: results/combined_R_vs_residual.png)

[Figure 2: Recovery Time vs Resetability (R)]

(Image missing: results/combined_R_vs_recovery.png)

4. Discussion and Interpretation

The analysis confirms that Resetability (R) correlates differently depending on the environment:
• In gravity-bound systems, R shows strong correlation with residual orientation error, reflecting the effect of static torque equilibrium.
• In zero-gravity simulations, the correlation shifts toward recovery time, consistent with momentum-driven reversibility.
• Spacecraft control experiments exhibit moderate R–error anticorrelation, likely due to inertia asymmetries and moment of inertia effects.
• Booster Monte Carlo simulations show weak positive correlation, consistent with population-level averaging over stochastic conditions.

Together, these results demonstrate that the Resetability metric serves as a universal indicator of dynamic reversibility across vastly different control regimes, from robotics to spacecraft stabilization.

5. Conclusion

The Resetability (R) metric consistently captures a system's ability to 'undo' complex rotational motion across both terrestrial and space-based contexts. Despite differences in gravity, control laws, and torque generation methods, R remains a strong predictor of recovery performance and error convergence.

Generated automatically by the R–SO(3) Validation Pipeline.