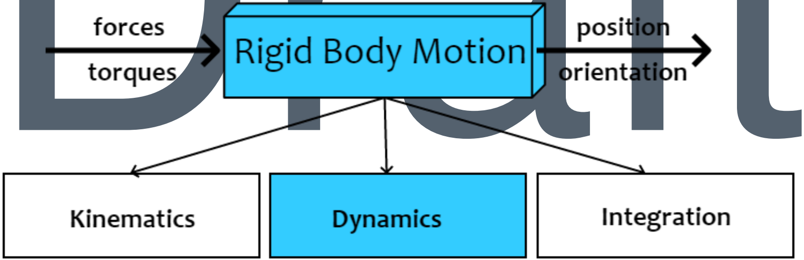
Dynamics Eqs of Rigid Body Motion

Lecture 6



Agenda

Lecture 6 | Dynamics

- Newton's laws of motion for point masses/particles
- Euler's laws of motion for rigid body
  - Translational equation of motion
  - Rotational equation of motion

Newton's Laws of Motion

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Second Law

In an inertial reference frame, the sum of forces on a point mass/particle object is equal to mass of the object times the acceleration of the object,

$$\underbrace{\sum_k \boldsymbol{f}_k^e}_{\boldsymbol{f}_{total}} = m\boldsymbol{a}^e = m\ddot{\boldsymbol{p}}^e \Leftrightarrow \sum_k \begin{bmatrix} f_{k,x}^e \\ f_{k,y}^e \\ f_{k,z}^e \end{bmatrix} = m \begin{bmatrix} a_x^e \\ a_y^e \\ a_z^e \end{bmatrix} = m \begin{bmatrix} \ddot{p}_x^e \\ \ddot{p}_y^e \\ \ddot{p}_z^e \end{bmatrix} \tag{1}$$

- For the purpose of studying quadrotor flight, the earth-fixed frame as used in the previous lectures is an inertial frame

Newton's Laws of Motion

Law of Action and Reaction

When a particle exerts a force on a second particle (upon some form of interaction, contact or at-a-distance), the second particle simultaneously exerts an equal in magnitude, opposite in direction, force onto the first particle.

- The direction of the two forces is along the straight line joining the point masses
- If i and j are two particles, and $\boldsymbol{f}_{ij}$ is the force with which particle i acts upon particle j, and $\boldsymbol{r}_i$ and $\boldsymbol{r}_j$ are position vectors then

$$\boldsymbol{f}_{ij} = -\boldsymbol{f}_{ji} \quad (2a) \qquad\qquad \boldsymbol{f}_{ij} = \pm \left\| \boldsymbol{f}_{ij} \right\| (\boldsymbol{r}_i - \boldsymbol{r}_j) \quad (2b)$$

Rigid Body

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A rigid body object can be seen as system consisting of a very large (in the limit infinite) number of small (in the limit infinitesimal) point-mass particles, with the property that the relative positions of the particles wrt each other are constant (rigidity).

Translational Dynamic Equation

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Let's take a system of N particles. There are two types of forces acting on each particle i: external system forces (from objects external to the system), and internal system forces (from the other particles).

$$\sum_k \boldsymbol{f}^e_{ik} + \sum_j \boldsymbol{f}^e_{ji} = m_i \boldsymbol{a}^e_i \tag{3}$$

$$\underbrace{\sum_k \sum_i \boldsymbol{f}^e_{ik}}_{=\boldsymbol{f}^e_{\text{ext, total}}} + \underbrace{\sum_i \sum_j \boldsymbol{f}^e_{ji}}_{=0,\ \text{since } \boldsymbol{f}_{ji} = -\boldsymbol{f}_{ij}} = \sum_i m_i \boldsymbol{a}^e_i \tag{4}$$

Translation & Center of Mass

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$$\sum m_i \boldsymbol{a}_i^e = \sum m_i \ddot{\boldsymbol{r}}_i^e = m \frac{d^2}{dt^2} \underbrace{\left(\frac{1}{m} \sum m_i \boldsymbol{r}_i^e \right)}_{\triangleq \boldsymbol{p}^e}$$

$$\boxed{\boldsymbol{p} = \frac{1}{m} \sum_i m_i \boldsymbol{r}_i} \tag{5}$$

$$\boxed{\boldsymbol{f}^e_{\text{ext, total}} = m \ddot{\boldsymbol{p}}^e = m \boldsymbol{a}_p^e} \tag{6}$$

where $\boldsymbol{r}$ is the center of mass position vector, and $m = \sum_i m_i$ is the total mass of the system. The sum of external forces equals the mass of the system multiplied with the acceleration of the center of mass.

Torque

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Because of the rigidity constraint, forces do not only push or pull an object through space (translate it), but also tend to rotate it. This effect is expressed by the torque.

“Torque is the tendency of a force to turn or twist. If a force is used to begin to spin an object or to stop an object from spinning, a torque is made” (wikipedia)

Torque

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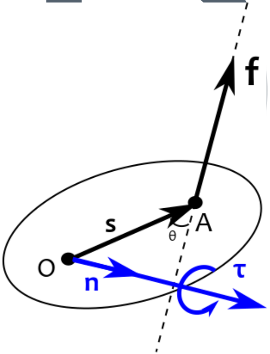

Let $\boldsymbol{f}$ be an external force acting on a body, and point O not on the line of operation of the force. And let vector $\boldsymbol{s}$ be defined by point O and any point on the line of action of the force $\boldsymbol{f}$. Then the torque about point O will be

$$\tau_O = [\boldsymbol{s}]_\times \boldsymbol{f} = \|\boldsymbol{s}\| \, \|\boldsymbol{f}\| \sin(\theta) \boldsymbol{n} \qquad (7)$$

Torque

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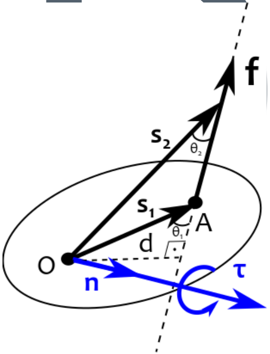

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$$\tau_O = [\boldsymbol{s}]_\times \boldsymbol{f} = \|f\| \cdot d \cdot \boldsymbol{n} \qquad (8)$$

Fixed, Sliding and Free vectors

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- Position vector - is a fixed vector, its initial point is determined by the coordinate system or reference frame
- Force in the context of a rigid body study is a sliding vector, meaning its initial point can be anywhere on the line of operation
- Velocity, acceleration - are free vectors, only the magnitude and direction that are relevant

Rotational Equation of Motion

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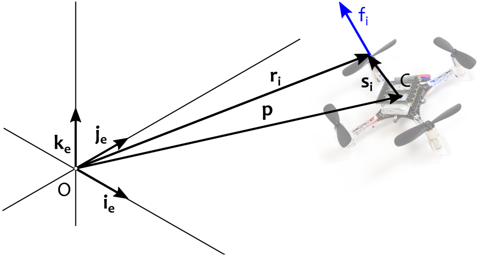

…tion, … rnal force

$$\boldsymbol{r}_i = \boldsymbol{p} + \boldsymbol{s}_i$$

$$[\boldsymbol{r}_i]_\times = [\boldsymbol{p}]_\times + [\boldsymbol{s}_i]_\times$$

$$[\boldsymbol{r}_i]_\times \boldsymbol{f}_i = [\boldsymbol{p}]_\times \boldsymbol{f}_i + [\boldsymbol{s}_i]_\times \boldsymbol{f}_i$$

$$\sum_i \tau_{O,i} = [\boldsymbol{p}]_\times \sum_i \boldsymbol{f}_i + \sum_i \tau_{C,i}$$

$$\boxed{\tau_{O,ext} = [\boldsymbol{p}]_\times \boldsymbol{f}_{total,ext} + \tau_{C,ext}} \qquad (9)$$

Rotational Equation of Motion

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Second relation, starting from Netwons Second law for a system of particles

$$\boldsymbol{f}_i^e + \sum_j \boldsymbol{f}_{ji}^e = m_i \boldsymbol{a}_i^e$$

$$[\boldsymbol{r}_i^e]_\times \boldsymbol{f}_i^e + \sum_j [\boldsymbol{r}_i^e]_\times \boldsymbol{f}_{ji}^e = m_i [\boldsymbol{r}_i^e]_\times \boldsymbol{a}_i^e$$

$$\sum_i [\boldsymbol{r}_i^e]_\times \boldsymbol{f}_i^e + \sum_i \sum_j [\boldsymbol{r}_i^e]_\times \boldsymbol{f}_{ji}^e = \sum_i m_i [\boldsymbol{r}_i^e]_\times \boldsymbol{a}_i^e$$

$$\tau_{O,ext}^e + (\dots [\boldsymbol{r}_i^e]_\times \boldsymbol{f}_{ji}^e - [\boldsymbol{r}_j^e]_\times \boldsymbol{f}_{ji}^e \dots) = \sum_i m_i [\boldsymbol{r}_i^e]_\times \boldsymbol{a}_i^e$$

Rotational Equation of Motion

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$$[\boldsymbol{r}_i^e]_\times \boldsymbol{f}_{ji}^e - [\boldsymbol{r}_j^e]_\times \boldsymbol{f}_{ji}^e = [\boldsymbol{r}_i^e - \boldsymbol{r}_j^e]_\times (\pm)\|\boldsymbol{f}_{ji}\| (\boldsymbol{r}_i^e - \boldsymbol{r}_j^e) = 0 = \boldsymbol{\tau}_{O,int}$$

So,

$$\boxed{\boldsymbol{\tau}_O^e = \sum_i m_i \, [\boldsymbol{r}_i^e]_\times \, \boldsymbol{a}_i^e} \tag{10}$$

Rotational Equation of Motion

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We next look at the right hand side term, and begin to expand

$$\sum_i m_i \left[\boldsymbol{r}_i^e\right]_\times \boldsymbol{a}_i^e = \sum_i m_i \left[\boldsymbol{p}^e + \boldsymbol{s}_i^e\right]_\times \boldsymbol{a}_i^e$$

from the kinematics lecture we know that

$$\boldsymbol{a}_i^e = \boldsymbol{a}_p^e + \left[\alpha^e\right]_\times \boldsymbol{s}_i^e + \left[\omega^e\right]_\times \left[\omega^e\right]_\times \boldsymbol{s}_i^e$$

thus

$$\begin{aligned} \tau_O^e &= \sum_i m_i \left[\boldsymbol{p}^e + \boldsymbol{s}_i^e\right]_\times \left(\boldsymbol{a}_p^e + \left[\alpha^e\right]_\times \boldsymbol{s}_i^e + \left[\omega^e\right]_\times \left[\omega^e\right]_\times \boldsymbol{s}_i^e\right) \\ &= \boldsymbol{T}_1 + \boldsymbol{T}_2 + \boldsymbol{T}_3 + \boldsymbol{T}_4 + \boldsymbol{T}_5 + \boldsymbol{T}_6 \end{aligned}$$

Rotational Equation of Motion

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$$\boldsymbol{T}_1 = \sum_i m_i [\boldsymbol{p}^e]_\times a_p^e = m [\boldsymbol{p}^e]_\times a_p^e = [\boldsymbol{p}^e]_\times F_{total,ext}$$

$$\boldsymbol{T}_2 = \sum_i m_i [\boldsymbol{p}^e]_\times [\omega^e]_x \boldsymbol{s}_i^e = [\boldsymbol{p}^e]_\times [\omega^e]_\times \sum_i m_i \boldsymbol{s}_i^e =$$

This is because $\boldsymbol{p} = \frac{1}{m}\sum_i m_i \boldsymbol{r}_i = \frac{1}{m}\sum_i (m_i \boldsymbol{p} + m_i \boldsymbol{s}_i) = \boldsymbol{p} + \frac{1}{m}\sum_i m_i \boldsymbol{s}_i \Rightarrow$

$$\sum_i m_i \boldsymbol{s}_i = 0 \tag{11}$$

Rotational Equation of Motion

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$$\boldsymbol{T}_3 = \sum_i m_i \left[\boldsymbol{p}^e\right]_\times \left[\boldsymbol{\omega}^e\right]_\times \left[\boldsymbol{\omega}^e\right]_\times \boldsymbol{s}_i^e = \left[\boldsymbol{p}^e\right]_\times \left[\boldsymbol{\omega}^e\right]_\times \left[\boldsymbol{\omega}^e\right]_\times \sum_i m_i \boldsymbol{s}_i^e = 0$$

$$\boldsymbol{T}_4 = \sum_i m_i \left[\boldsymbol{s}_i^e\right]_\times \boldsymbol{a}_p^e = \left[\sum_i m_i \boldsymbol{s}_i^e\right]_\times \boldsymbol{a}_p^e = 0$$

$$\boldsymbol{T}_5 = \sum_i m_i \left[\boldsymbol{s}_i^e\right]_\times \left[\alpha^e\right]_x \boldsymbol{s}_i^e = \underbrace{-\sum_i m_i \left[\boldsymbol{s}_i^e\right]_\times \left[\boldsymbol{s}_i^e\right]_x}_{\mathbf{J}^e} \alpha^e = \mathbf{J}^e \alpha^e$$

where we used the fact that $\left[\boldsymbol{a}\right]_\times \boldsymbol{b} = -\left[\boldsymbol{b}\right]_\times \boldsymbol{a}$.

Rotational Equation of Motion

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$$
\begin{aligned}
\boldsymbol{T}_6 &= \sum_i m_i \left[\boldsymbol{s}_i^e\right]_\times \left[\omega^e\right]_\times \overbrace{\left[\omega^e\right]_\times \boldsymbol{s}_i^e} = -\sum_i \underbrace{m_i \left[\boldsymbol{s}_i^e\right]_\times \left[\omega^e\right]_\times \left[\boldsymbol{s}_i^e\right]_\times} \omega^e = \\
&= -\sum_i m_i \left(\left[\left[\boldsymbol{s}_i^e\right]_\times \omega^e\right]_\times + \left[\omega^e\right]_\times \left[\boldsymbol{s}_i^e\right]_\times \right) \left[\boldsymbol{s}_i^e\right]_\times \omega^e \\
&= -\sum_i m_i \left[\omega^e\right]_\times \left[\boldsymbol{s}_i^e\right]_\times \left[\boldsymbol{s}_i^e\right]_\times \omega^e = \left[\omega^e\right]_\times \underbrace{\left(-\sum_i m_i \left[\boldsymbol{s}_i^e\right]_\times \left[\boldsymbol{s}_i^e\right]_\times \right)}_{\mathbf{J}^e} \omega^e
\end{aligned}
$$

We used the following relations $\left[[a]_\times \boldsymbol{b}\right]_\times = [a]_\times [b]_\times - [b]_\times [a]_\times$, such that $[a]_\times [b]_\times = \left[[a]_\times \boldsymbol{b}\right]_\times + [b]_\times [a]_\times$, and $[\boldsymbol{a}]_\times \boldsymbol{a} = 0$

Rotational Equation of Motion

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$$\tau_O^e = T_1 + \dots + T_6$$

$$\tau_O^e - [s^e]_\times \boldsymbol{f}_{tot,ext}^e = \mathbf{J}^e \alpha^e + [\omega^e]_\times \mathbf{J}^e \omega^e$$

If we use eq (9) to obtain the rotational eq of motion a

$$\boxed{\tau_C^e = \mathbf{J}^e \alpha^e + [\omega^e]_\times \mathbf{J}^e \omega^e} \tag{12}$$

where

$$\boxed{\mathbf{J}^e = -\sum_i m_i \, [\boldsymbol{s}_i^e]_\times \, [\boldsymbol{s}_i^e]_\times} \tag{13}$$

Rotational Equation of Motion

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We are also interested in expressing the rotational equation of motion in body-frame coordinates. We'll can do some algebra to obtain that

$$\boxed{\boldsymbol{\tau}_c^b = \mathbf{J}^b \boldsymbol{\alpha}^b + \left[\boldsymbol{\omega}^b\right]_\times \mathbf{J}^b \boldsymbol{\omega}^b}, \tag{14}$$

where $\boxed{\mathbf{J}^b = \mathbf{R}_e^b \mathbf{J}^e \mathbf{R}_b^e}$ and we used the fact that $[\mathbf{A}\boldsymbol{a}]_\times = \mathbf{A}\left[\boldsymbol{a}\right]_\times \mathbf{A}^T$.
And finally, we can also express the relation as:

$$\boxed{\boldsymbol{\alpha}^b = \dot{\boldsymbol{\omega}}^b = \left(\mathbf{J}^b\right)^{-1}\left(-\left[\omega^b\right]_\times \mathbf{J}^b \boldsymbol{\omega}^b + \boldsymbol{\tau}_c^b\right)} \tag{15}$$

Inertia Matrix

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- The global inertia matrix $\mathbf{J}^e$ was expressed in terms of the body inertia matrix $\mathbf{J}^b$ by the following

$$\mathbf{J}^e = -\sum_i m_i \left[\boldsymbol{s}_i^e\right]_\times \left[\boldsymbol{s}_i^e\right]_\times = -\sum_i m_i \left[\mathbf{R}_b^e \boldsymbol{s}_i^b\right]_\times \left[\mathbf{R}_b^e \boldsymbol{s}_i^b\right]_\times$$

$$= -\sum_i m_i \mathbf{R}_b^e \left[\boldsymbol{s}_i^b\right]_\times \underbrace{\mathbf{R}_e^b \mathbf{R}_b^e}_{\mathbf{I}_3} \left[\boldsymbol{s}_i^b\right]_\times \mathbf{R}_e^b = \mathbf{R}_b^e \underbrace{\left(-\sum_i m_i \left[\boldsymbol{s}_i^b\right]_\times \left[\boldsymbol{s}_i^b\right]_\times\right)}_{\mathbf{J}^b} \mathbf{R}_e^b$$

- While $\boldsymbol{s}_e^b$ is variable in time, vector $\boldsymbol{s}_i^b$ is constant, meaning $\mathbf{J}^e$ is time dependent, while $\mathbf{J}^b$ is constant

Inertia Matrix

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$$\mathbf{J}^b = -\sum_i m_i \left[\boldsymbol{s}_i^b\right]_\times \left[\boldsymbol{s}_i^b\right]_\times = \sum_i m_i \begin{bmatrix} 0 & -z_i & y_i \\ z_i & 0 & -x_i \\ -y_i & x_i & 0 \end{bmatrix} \begin{bmatrix} 0 & -z_i & y_i \\ z_i & 0 & -x_i \\ -y_i & x_i & 0 \end{bmatrix}$$

$$\mathbf{J}^b = \sum_i m_i \begin{bmatrix} y_i^2 + z_i^2 & -x_i y_i & -x_i z_i \\ -x_i y_i & x_i^2 + z_i^2 & -y_i z_i \\ -x_i z_i & -y_i z_i & x_i^2 + y_i^2 \end{bmatrix}, \text{ where } \boldsymbol{s}_i^b = \begin{bmatrix} x_i \\ y_i \\ z_i \end{bmatrix} \tag{16}$$

$$\mathbf{J}^b = \begin{bmatrix} \int_V (y_i^2 + z_i^2) dm & -\int_V x_i y_i dm & -\int_V x_i z_i dm \\ -\int_V x_i y_i dm & \int_V (x_i^2 + z_i^2) dm & -\int_V y_i z_i dm \\ -\int_V x_i z_i dm & -\int_V y_i z_i dm & \int_V (x_i^2 + y_i^2) dm \end{bmatrix} \tag{17}$$

Onto the quiz