



Robotics 2

Dynamic model of robots: Algorithm for computing kinetic energy

Prof. Alessandro De Luca

DIPARTIMENTO DI INGEGNERIA INFORMATICA
AUTOMATICA E GESTIONALE ANTONIO RUBERTI



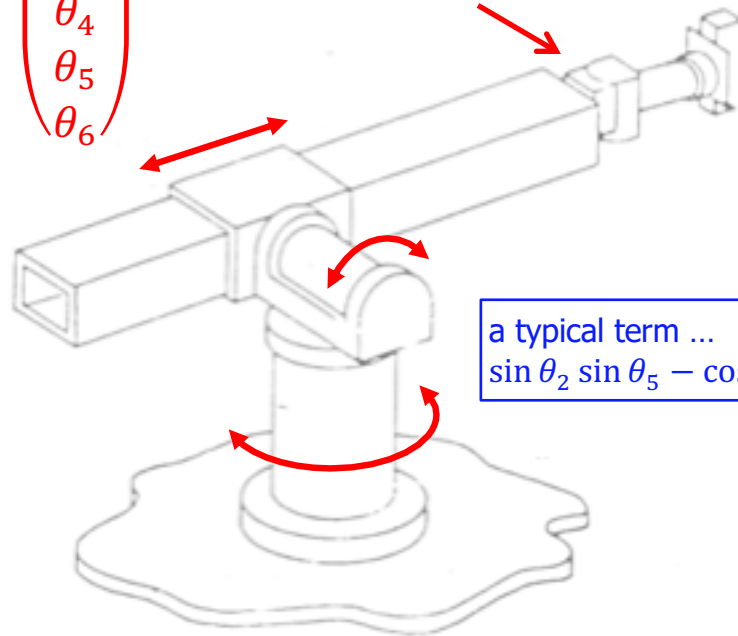
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Complexity of robot inertia terms

element $m_{11}(q)$ of Stanford arm

$$q = \begin{pmatrix} \theta_1 \\ \theta_2 \\ d_3 \\ \theta_4 \\ \theta_5 \\ \theta_6 \end{pmatrix}$$

3R spherical wrist



a typical term ...
 $\sin \theta_2 \sin \theta_5 - \cos \theta_2 \sin \theta_4 \cos \theta_5$

radius of gyration factors k_{ijk}^2 are being used here for a body of mass m and moment of inertia I w.r.t. an axis, the radius of gyration k is the distance of a point mass m from the same axis, such that its moment of inertia is I

$$m_{11} = m_1 k_{122}^2$$

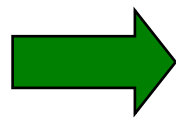
... (derived by hand) in JPL
 Tech. Memo. 33-669, 1974

$$\begin{aligned} &+ m_2 \left[k_{211}^2 s^2 \theta_2 + k_{233}^2 c^2 \theta_2 + r_2 (2\bar{y}_2 + r_2) \right] \\ &+ m_3 \left[k_{322}^2 s^2 \theta_2 + k_{333}^2 c^2 \theta_2 + r_3 (2\bar{z}_3 + r_3) s^2 \theta_2 + r_2^2 \right] \\ &+ m_4 \left\{ \frac{1}{2} k_{411}^2 \left[s^2 \theta_2 (2s^2 \theta_4 - 1) + s^2 \theta_4 \right] + \frac{1}{2} k_{422}^2 (1 + c^2 \theta_2 + s^2 \theta_4) \right. \\ &\quad \left. + \frac{1}{2} k_{433}^2 \left[s^2 \theta_2 (1 - 2s^2 \theta_4) - s^2 \theta_4 \right] + r_3^2 s^2 \theta_2 + r_2^2 - 2\bar{y}_4 r_3 s^2 \theta_2 + 2\bar{z}_4 (r_2 s \theta_4 + r_3 s \theta_2 c \theta_2 c \theta_4) \right\} \\ &+ m_5 \left\{ \frac{1}{2} (-k_{511}^2 + k_{522}^2 + k_{533}^2) \left[(s \theta_2 s \theta_5 - c \theta_2 s \theta_4 c \theta_5)^2 + c^2 \theta_4 c^2 \theta_5 \right] \right. \\ &\quad \left. + \frac{1}{2} (-k_{511}^2 - k_{522}^2 + k_{533}^2) (s^2 \theta_4 + c^2 \theta_2 c^2 \theta_4) \right. \\ &\quad \left. + \frac{1}{2} (k_{511}^2 + k_{522}^2 - k_{533}^2) \left[(s \theta_2 c \theta_5 + c \theta_2 s \theta_4 s \theta_5)^2 + c^2 \theta_4 s^2 \theta_5 \right] + r_3^2 s^2 \theta_2 + r_2^2 \right. \\ &\quad \left. + 2\bar{z}_5 \left[r_3 (s^2 \theta_2 c \theta_5 + s \theta_2 s \theta_4 c \theta_4 s \theta_5) - r_2 c \theta_4 s \theta_5 \right] \right\} \\ &+ m_6 \left\{ \frac{1}{2} (-k_{611}^2 + k_{622}^2 + k_{633}^2) \left[(s \theta_2 s \theta_5 c \theta_6 - c \theta_2 s \theta_4 c \theta_5 c \theta_6 - c \theta_2 c \theta_4 s \theta_6)^2 + (c \theta_4 c \theta_5 c \theta_6 - s \theta_4 s \theta_6)^2 \right] \right. \\ &\quad \left. + \frac{1}{2} (k_{611}^2 - k_{622}^2 + k_{633}^2) \left[(c \theta_2 s \theta_4 c \theta_5 s \theta_6 - s \theta_2 s \theta_5 s \theta_6 - c \theta_2 c \theta_4 c \theta_6)^2 + (c \theta_4 c \theta_5 s \theta_6 + s \theta_4 c \theta_6)^2 \right] \right. \\ &\quad \left. + \frac{1}{2} (k_{611}^2 + k_{622}^2 - k_{633}^2) \left[(c \theta_2 s \theta_4 s \theta_5 + s \theta_2 c \theta_5)^2 + c^2 \theta_4 s^2 \theta_5 \right] \right. \\ &\quad \left. + \left[r_6 c \theta_2 s \theta_4 s \theta_5 + (r_6 c \theta_5 + r_3) s \theta_2 \right]^2 + (r_6 c \theta_4 s \theta_5 - r_2)^2 \right. \\ &\quad \left. + 2\bar{z}_6 \left[r_6 (s^2 \theta_2 c^2 \theta_5 + c^2 \theta_4 s^2 \theta_5 + c^2 \theta_2 s^2 \theta_4 s^2 \theta_5 + 2s \theta_2 c \theta_2 s \theta_4 s \theta_5 c \theta_5) \right. \right. \\ &\quad \left. \left. + r_3 (s \theta_2 c \theta_2 s \theta_4 s \theta_5 + s^2 \theta_2 c \theta_5) - r_2 c \theta_4 s \theta_5 \right] \right\} \end{aligned}$$

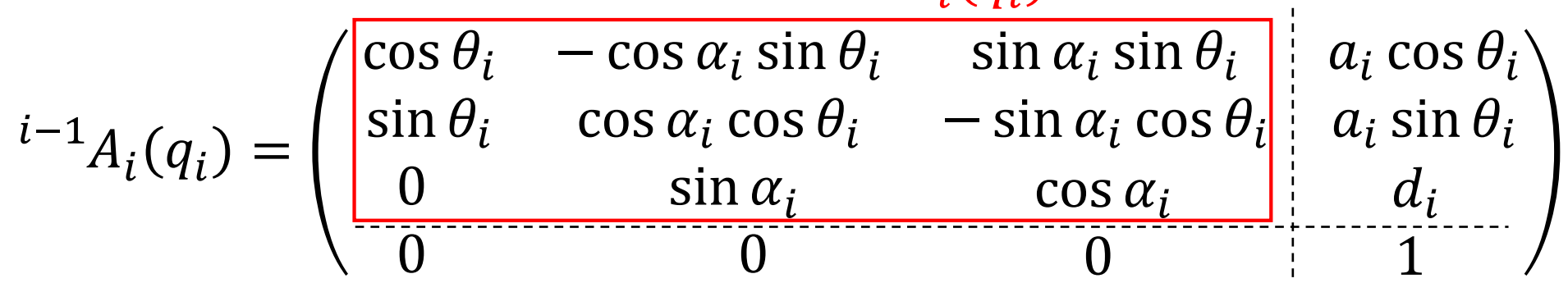


Expression of v_{ci} and ω_i

- v_{ci} and ω_i can be written using the relations of the robot differential kinematics (partial Jacobians)
- it is useful however to operate in a **recursive** way, expressing each vector quantity related to link i in the “**moving**” frame RF_i attached to link i (with the notation **${}^i\text{vector}_i$**)
 - particularly convenient when using algebraic/symbolic manipulation languages (Matlab Symbolic Toolbox, Maple, Mathematica, ...) for computing the kinetic energy of a (open chain) robot arm, when the number of joints increases (e.g., for $N \geq 4$)



Moving Frames





Moving Frames algorithm

velocity of
center of mass
of link i

$$\vec{v}_{ci} = \vec{v}_i + \omega_i \times \vec{r}_{ci}$$

velocity of O_i
(origin of RF_i)

angular velocity
of link i

position of
center of mass
of link i w.r.t. O_i

$$\text{set } \sigma_i = \begin{cases} 0 & \text{revolute joint} \\ 1 & \text{prismatic joint} \end{cases}$$

$${}^i\omega_i = {}^{i-1}R_i^T(q_i) \left[{}^{i-1}\omega_{i-1} + (1 - \sigma_i) \dot{q}_i {}^{i-1}z_{i-1} \right] = {}^{i-1}R_i^T(q_i) {}^{i-1}\omega_i$$

z -axis of RF_{i-1}

$$\begin{pmatrix} 0 \\ 0 \\ 1 \end{pmatrix}$$

$${}^i\vec{v}_i = {}^{i-1}R_i^T(q_i) \left[{}^{i-1}\vec{v}_{i-1} + \sigma_i \dot{q}_i {}^{i-1}z_{i-1} + {}^{i-1}\omega_i \times {}^{i-1}\vec{r}_{i-1,i} \right]$$

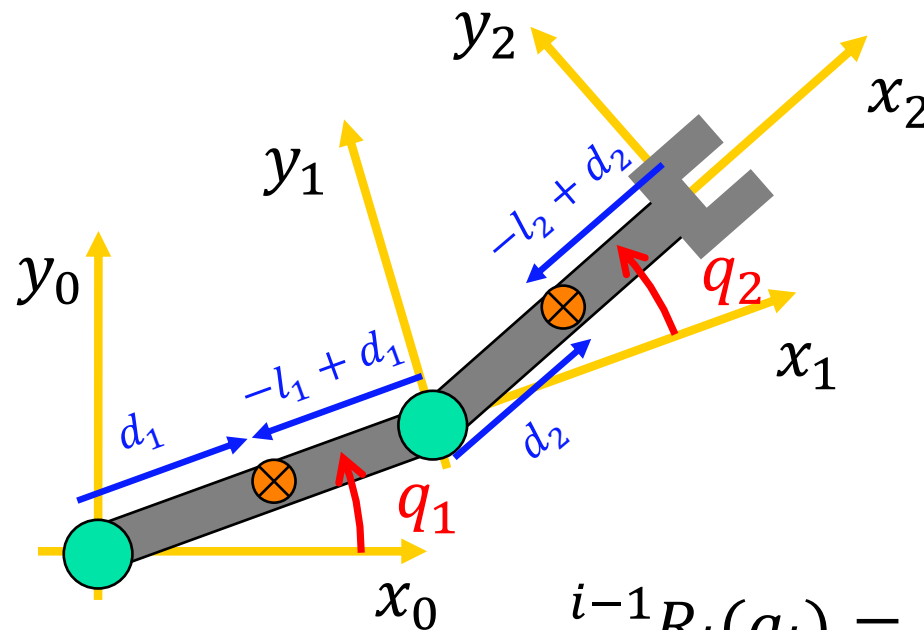
... = ${}^i\omega_i$ already computed

... = ${}^i\vec{r}_{i-1,i}$ (constant,
if joint i is revolute!)



Dynamic model of a 2R robot

application of the algorithm



$\sigma_i = 0, \quad i = 1, 2$
(revolute joints)

moving in the
vertical plane

$$g = \begin{pmatrix} 0 \\ -g_0 \\ 0 \end{pmatrix}$$

$$g_0 = 9.81$$

$${}^{i-1}R_i(q_i) = \begin{pmatrix} c_i & -s_i & 0 \\ s_i & c_i & 0 \\ 0 & 0 & 1 \end{pmatrix} \quad {}^i r_{ci} = \begin{pmatrix} -l_i + d_i \\ 0 \\ 0 \end{pmatrix}$$

assumption: center of mass of
each link is on its kinematic axis

initialization: $i = 0$

$${}^0\omega_0 = 0$$

$${}^0v_0 = 0$$



First step (link 1)

$$i = 1$$

$${}^1\omega_1 = {}^0R_1^T(q_1) \left[{}^0\omega_0 + \dot{q}_1 \begin{pmatrix} 0 \\ 0 \\ 1 \end{pmatrix} \right] = \begin{pmatrix} 0 \\ 0 \\ \dot{q}_1 \end{pmatrix}$$

$$\begin{aligned} {}^1v_1 &= {}^0R_1^T(q_1) \left[{}^0v_0 + \begin{pmatrix} 0 \\ 0 \\ \dot{q}_1 \end{pmatrix} \times \begin{pmatrix} l_1 c_1 \\ l_1 s_1 \\ 0 \end{pmatrix} \right] = {}^0R_1^T(q_1) \begin{pmatrix} 0 \\ 0 \\ \dot{q}_1 \end{pmatrix} \times {}^0R_1^T(q_1) \begin{pmatrix} l_1 c_1 \\ l_1 s_1 \\ 0 \end{pmatrix} \\ &= \begin{pmatrix} 0 \\ 0 \\ \dot{q}_1 \end{pmatrix} \times \begin{pmatrix} l_1 \\ 0 \\ 0 \end{pmatrix} = \begin{pmatrix} 0 \\ l_1 \dot{q}_1 \\ 0 \end{pmatrix} \end{aligned}$$

$${}^1v_{c1} = \begin{pmatrix} 0 \\ l_1 \dot{q}_1 \\ 0 \end{pmatrix} + \begin{pmatrix} 0 \\ 0 \\ \dot{q}_1 \end{pmatrix} \times \begin{pmatrix} -l_1 + d_1 \\ 0 \\ 0 \end{pmatrix} = \begin{pmatrix} 0 \\ d_1 \dot{q}_1 \\ 0 \end{pmatrix}$$



Kinetic energy of link 1

$${}^1\omega_1 = \begin{pmatrix} 0 \\ 0 \\ \dot{q}_1 \end{pmatrix}$$

$${}^1v_{c1} = \begin{pmatrix} 0 \\ d_1 \dot{q}_1 \\ 0 \end{pmatrix}$$



$$T_1 = \frac{1}{2} m_1 d_1^2 \dot{q}_1^2 + \frac{1}{2} I_{c1,zz} \dot{q}_1^2 = \frac{1}{2} \underbrace{(I_{c1,zz} + m_1 d_1^2)}_{\substack{\text{the actual inertia around the rotation axis} \\ \text{of the first joint (parallel axis theorem)}}} \dot{q}_1^2$$

the actual inertia around the rotation axis
of the first joint (parallel axis theorem)



Second step (link 2)

$$i = 2$$

$${}^2\omega_2 = {}^1R_2^T(q_2) \left[{}^1\omega_1 + \dot{q}_2 \begin{pmatrix} 0 \\ 0 \\ 1 \end{pmatrix} \right] = \begin{pmatrix} 0 \\ 0 \\ \dot{q}_1 + \dot{q}_2 \end{pmatrix}$$

$${}^2v_2 = {}^1R_2^T(q_2) \left[{}^1v_1 + \begin{pmatrix} 0 \\ 0 \\ \dot{q}_1 + \dot{q}_2 \end{pmatrix} \times \begin{pmatrix} l_2 c_2 \\ l_2 s_2 \\ 0 \end{pmatrix} \right] = \begin{pmatrix} l_1 s_2 \dot{q}_1 \\ l_1 c_2 \dot{q}_1 \\ 0 \end{pmatrix} + \begin{pmatrix} 0 \\ 0 \\ \dot{q}_1 + \dot{q}_2 \end{pmatrix} \times \begin{pmatrix} l_2 \\ 0 \\ 0 \end{pmatrix}$$

$$= \begin{pmatrix} l_1 s_2 \dot{q}_1 \\ l_1 c_2 \dot{q}_1 + l_2 (\dot{q}_1 + \dot{q}_2) \\ 0 \end{pmatrix}$$



Kinetic energy of link 2

$$i = 2$$

$${}^2v_{c2} = {}^2v_2 + \begin{pmatrix} 0 \\ 0 \\ \dot{q}_1 + \dot{q}_2 \end{pmatrix} \times \begin{pmatrix} -l_2 + d_2 \\ 0 \\ 0 \end{pmatrix} = \begin{pmatrix} l_1 s_2 \dot{q}_1 \\ l_1 c_2 \dot{q}_1 + d_2 (\dot{q}_1 + \dot{q}_2) \\ 0 \end{pmatrix}$$



$$T_2 = \frac{1}{2} m_2 \left(l_1^2 \dot{q}_1^2 + d_2^2 (\dot{q}_1 + \dot{q}_2)^2 + 2 l_1 d_2 c_2 \dot{q}_1 (\dot{q}_1 + \dot{q}_2) \right) + \frac{1}{2} I_{c2,zz} (\dot{q}_1 + \dot{q}_2)^2$$



Robot inertia matrix

$$T = T_1 + T_2 = \frac{1}{2} (\dot{q}_1 \quad \dot{q}_2)^T \begin{pmatrix} m_{11}(q) & m_{12}(q) \\ m_{21}(q) & m_{22}(q) \end{pmatrix} \begin{pmatrix} \dot{q}_1 \\ \dot{q}_2 \end{pmatrix}$$

$$\begin{aligned} m_{11}(q) &= I_{c1,zz} + m_1 d_1^2 + I_{c2,zz} + m_2 d_2^2 + m_2 l_1^2 + 2m_2 l_1 d_2 c_2 \\ &= a_1 + 2a_2 \cos q_2 \end{aligned}$$

$$m_{12}(q) = m_{21}(q) = I_{c2,zz} + m_2 d_2^2 + m_2 l_1 d_2 c_2 = a_3 + a_2 \cos q_2$$

$$m_{22} = I_{c2,zz} + m_2 d_2^2 = a_3$$

NOTE: introduction of **dynamic coefficients** a_i is a convenient **regrouping** of the dynamic parameters (more on this later → **linear parametrization of dynamics**)



Centrifugal and Coriolis terms

$$C_1(q) = \frac{1}{2} \left(\frac{\partial M_1}{\partial q} + \left(\frac{\partial M_1}{\partial q} \right)^T - \frac{\partial M}{\partial q_1} \right) = \frac{1}{2} \left(\begin{pmatrix} 0 & -2a_2s_2 \\ 0 & -a_2s_2 \end{pmatrix} + \begin{pmatrix} 0 & 0 \\ -2a_2s_2 & -a_2s_2 \end{pmatrix} \right)$$
$$= \begin{pmatrix} 0 & -a_2s_2 \\ -a_2s_2 & -a_2s_2 \end{pmatrix} \quad \rightarrow \quad c_1(q, \dot{q}) = -a_2s_2(\dot{q}_2^2 + 2\dot{q}_1\dot{q}_2)$$

$$C_2(q) = \frac{1}{2} \left(\frac{\partial M_2}{\partial q} + \left(\frac{\partial M_2}{\partial q} \right)^T - \frac{\partial M}{\partial q_2} \right) = \dots = \begin{pmatrix} a_2s_2 & 0 \\ 0 & 0 \end{pmatrix}$$

$$c_2(q, \dot{q}) = a_2s_2\dot{q}_1^2$$



Gravity terms

$$U_1 = -m_1 g^T r_{0,c1} = -m_1 \begin{pmatrix} 0 & -g_0 & 0 \end{pmatrix} \begin{pmatrix} * \\ d_1 s_1 \\ * \end{pmatrix} = m_1 g_0 d_1 s_1$$

$$U_2 = -m_2 g^T r_{0,c2} = m_2 g_0 (l_1 s_1 + d_2 s_{12})$$

$$U = U_1 + U_2$$

$$g(q) = \left(\frac{\partial U}{\partial q} \right)^T = \begin{pmatrix} g_0(m_1 d_1 c_1 + m_2 l_1 c_1 + m_2 d_2 c_{12}) \\ g_0 m_2 d_2 c_{12} \end{pmatrix} = \begin{pmatrix} a_4 c_1 + a_5 c_{12} \\ a_5 c_{12} \end{pmatrix}$$



Dynamic model of a 2R robot

$$(a_1 + 2a_2c_2)\ddot{q}_1 + (a_2c_2 + a_3)\ddot{q}_2 - a_2s_2(\dot{q}_2^2 + 2\dot{q}_1\dot{q}_2) + a_4c_1 + a_5c_{12} = u_1$$

$$(a_2c_2 + a_3)\ddot{q}_1 + a_3\ddot{q}_2 + a_2s_2\dot{q}_1^2 + a_5c_{12} = u_2$$

Q1: is it $a_2 = 0$ possible? ...physical interpretation? ...consequences?

Q2: is it $a_4 = a_5 = 0$ possible as well? ...physical interpretation?

Q3: based on the expressions of the dynamic coefficients a_1, a_2, a_3 , check that the robot inertia matrix is **always** positive definite, and in particular that the diagonal elements are **always** positive ($\forall q$)

Q4: provide two different matrices S' and S'' for the factorization of the quadratic velocity terms, respectively **satisfying** and **not satisfying** the skew-symmetry of $\dot{M} - 2S$