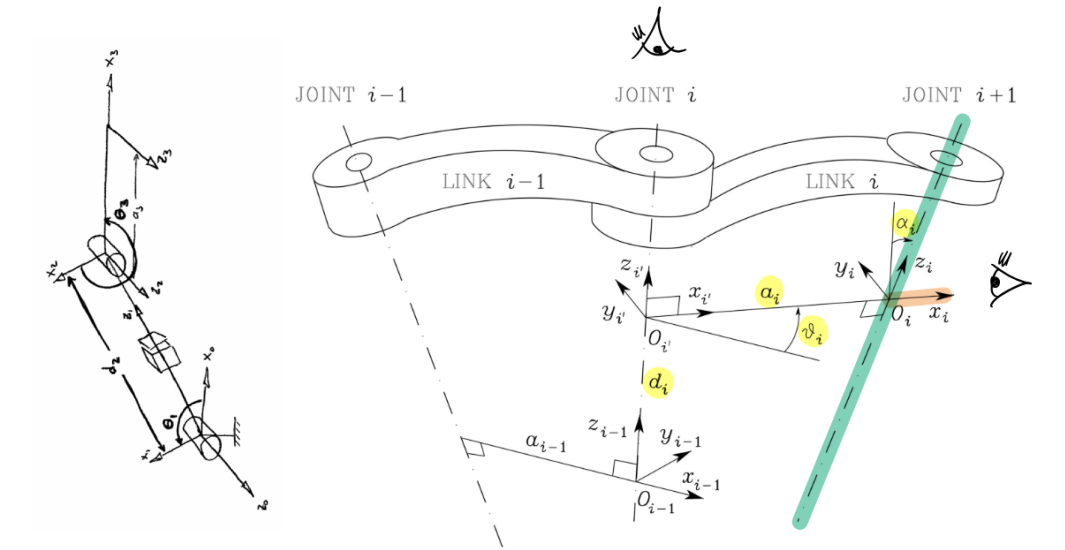


1. Denavit-Hartenberg



Il sistema di riferimento \mathcal{R}_i solidale con $LINK_i$ viene definito secondo le seguenti regole:

- ① **Asse z_i e origine O_i**
- L'asse z_i** è posto lungo l'asse di movimento di g_{i+1} (asse di rotazione o di traslazione a seconda del tipo di giunto)
 - L'origine O_i** è posta all'intersezione di z_i con la normale comune (*common normal*) fra gli assi z_{i-1} e z_i . La normale comune è quella retta perpendicolare ad entrambi gli assi (nota: entrambi angoli retti nella figura)
- Casi particolari:**
 - \mathcal{R}_0 :** origine O_0 e x_0 possono essere fissati a piacimento (solo z_0 univocamente definito).
 - \mathcal{R}_n :** $\nexists g_{n+1} \implies z_n, O_n$ non univocamente definiti. Per consuetudine: origine nel centro della pinza e z_n coincidente a a z_{n-1} (visto che tipicamente l'ultimo giunto è rotoidale).
- ② **Asse x_i e y_i**
- L'asse x_i** è fissato lungo la normale comune fra gli assi z_{i-1} e z_i
 - Se z_{i-1} e z_i si intersecano \implies direzione di x_i ($\perp z_i$) è arbitraria
 - se z_{i-1} e z_i sono paralleli \implies origine arbitraria, x_i nel piano normale a z_{i-1} e z_i con direzione e verso arbitrari.
- L'asse y_i** completa la terna destrorsa ($j = k \times i$)

③ Sistema di riferimento intermedio

$z_{i'}$ diretto lungo z_{i-1} | $O_{i'}$ posta all'intersezione di z_{i-1} con la normale comune fra z_{i-1} e z_i | $x_{i'}$ diretto lungo la normale comune fra z_{i-1} e z_i (come x_i)

- $d_i \rightarrow$ **link offset**: coordinata di $O_{i'}$ lungo z_{i-1}
- $\theta_i \rightarrow$ **joint angle**: angolo di rotazione da x_{i-1} a x_i attorno all'asse $z_{i'}$ (positivo quando la rotazione è anti-oraria)
- $a_i \rightarrow$ **link length**: distanza (con segno) fra O_i e $O_{i'}$
- $\alpha_i \rightarrow$ **link twist**: angolo di rotazione da z_{i-1} a z_i attorno all'asse x_i (positivo quando la rotazione è anti-oraria)

$${}^{i-1}\mathbf{T}_i(q_i) = \begin{bmatrix} c\theta_i & -s\theta_i c\alpha_i & s\theta_i s\alpha_i & a_i c\theta_i \\ s\theta_i & c\theta_i c\alpha_i & -c\theta_i s\alpha_i & a_i s\theta_i \\ 0 & s\alpha_i & c\alpha_i & d_i \\ 0 & 0 & 0 & 1 \end{bmatrix}$$

Trigonometric inequalities:

$c_{12} + s_{12} = c_{1-2}$ $c_{12} - s_{12} = c_{1+2}$ $s_1 c_2 - c_1 s_2 = s_{1-2}$ $s_1 c_2 + c_1 s_2 = s_{1+2}$

Tips:

$a \rightarrow \left\{ \begin{array}{l} z_{i-1} \xleftrightarrow{\text{dist.}} z_i \quad \text{along } x_i \\ \alpha_i \rightarrow \left\{ \begin{array}{l} z_{i-1} \xrightarrow{\quad} z_i \quad \text{around } x_i \\ d \rightarrow \left\{ \begin{array}{l} x_{i-1} \xleftrightarrow{\text{dist.}} x_i \quad \text{along } z_{i-1} \\ \theta \rightarrow \left\{ \begin{array}{l} x_{i-1} \xrightarrow{\quad} x_i \quad \text{around } z_{i-1} \end{array} \right. \end{array} \right. \end{array} \right.$

2. Differential Kinematics

2.1 Geometric Jacobian

i-th column of \mathbf{J} :

$$\begin{bmatrix} \mathbf{J}_{p,i} \\ \mathbf{J}_{o,i} \end{bmatrix} = \begin{cases} \begin{bmatrix} z_{i-1} \\ \mathbf{0} \end{bmatrix} & \text{for a \textit{prismatic} joint} \\ \begin{bmatrix} z_{i-1} \times (p - p_{i-1}) \\ z_{i-1} \end{bmatrix} & \text{for a \textit{revolute} joint} \end{cases}$$

$$\begin{bmatrix} 0 \\ 0 \\ 1 \end{bmatrix} \times \begin{bmatrix} x \\ y \\ z \end{bmatrix} = \begin{bmatrix} -y \\ x \\ 0 \end{bmatrix}$$

E.g. planar RRR

$$J(q) = \begin{bmatrix} z_0 \times (p - p_0) & z_1 \times (p - p_1) & z_2 \times (p - p_2) \\ z_0 & z_1 & z_2 \end{bmatrix} \quad \text{here } c_{12} = c(\theta_1 + \theta_2)$$

$${}^0T_0 = \begin{bmatrix} 1 & 0 & 0 & 0 \\ 0 & 1 & 0 & 0 \\ 0 & 0 & 1 & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix} \implies \mathbf{z_0} = \begin{bmatrix} 0 \\ 0 \\ 1 \end{bmatrix}, \quad \mathbf{p_0} = \begin{bmatrix} 0 \\ 0 \\ 0 \end{bmatrix}$$

$${}^0T_1 = \begin{bmatrix} c_1 & -s_1 & 0 & l_1 c_1 \\ s_1 & c_1 & 0 & l_1 s_1 \\ 0 & 0 & 1 & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix} \implies \mathbf{z_1} = \begin{bmatrix} 0 \\ 0 \\ 1 \end{bmatrix}, \quad \mathbf{p_1} = \begin{bmatrix} l_1 c_1 \\ l_1 s_1 \\ 0 \end{bmatrix}$$

$${}^0T_2 = {}^0T_1 {}^1T_2 = \begin{bmatrix} c_{12} & -s_{12} & 0 & l_1 c_1 + l_2 c_{12} \\ s_{12} & c_{12} & 0 & l_1 s_1 + l_2 s_{12} \\ 0 & 0 & 1 & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix} \implies \mathbf{z_2} = \begin{bmatrix} 0 \\ 0 \\ 1 \end{bmatrix}, \quad \mathbf{p_2} = \begin{bmatrix} l_1 c_1 + l_2 c_{12} \\ l_1 s_1 + l_2 s_{12} \\ 0 \end{bmatrix}$$

$${}^0T_3 = \begin{bmatrix} c_{123} & -s_{123} & 0 & l_1 c_1 + l_2 c_{12} + l_3 c_{123} \\ s_{123} & c_{123} & 0 & l_1 s_1 + l_2 s_{12} + l_3 s_{123} \\ 0 & 0 & 1 & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix} \implies \mathbf{p} = \begin{bmatrix} l_1 c_1 + l_2 c_{12} + l_3 c_{123} \\ l_1 s_1 + l_2 s_{12} + l_3 s_{123} \\ 0 \end{bmatrix}$$

2.2 Analytical Jacobian

$$\dot{x} = \begin{bmatrix} \dot{p} \\ \dot{\phi} \end{bmatrix} = \frac{dx}{dt} = \underbrace{\frac{\partial x}{\partial q}}_{J_A(q)} \underbrace{\frac{dq}{dt}}_{\dot{q}} = J_A(q) \dot{q}$$

$$J(q) = \begin{bmatrix} I & \mathbf{0} \\ \mathbf{0} & T(\phi) \end{bmatrix} J_A(q)$$

2.3 Inverse differential kinematics

$$\begin{cases} \text{minimize} & g(\dot{q}) = \frac{1}{2} \dot{q}^T W \dot{q} \\ \text{subject to} & v = J(q) \dot{q} \end{cases} \quad \begin{matrix} W \equiv I \\ \iff \end{matrix} \quad \dot{q} = J^\dagger(q) v \quad J^\dagger \triangleq J^T (J J^T)^{-1}$$

$$\begin{cases} \text{minimize} & g'(\dot{q}) = \frac{1}{2} (\dot{q} - \dot{q}_d)^T (\dot{q} - \dot{q}_d) \\ \text{subject to} & v = J(q) \dot{q} \end{cases} \iff \dot{q} = J^\dagger(q) v + \underbrace{(I - J^\dagger J)}_{\text{👉 in } \mathcal{N}} \dot{q}_d$$

Damped least-square:

$$J = U \Sigma V^T, \Sigma_{ii} = \sqrt{eig(J J^T)_i} \implies J^\dagger = V \Sigma^\dagger U^T \quad \sigma_i \mapsto 1/(\sigma_i + k^2) \quad J^* = J^T (J J^T + k^2 I)^{-1}$$

Secondary objectives:

$$\dot{H} = \frac{dH}{dt} = \frac{\partial H}{\partial q} \frac{dq}{dt} = \frac{\partial H}{\partial q} \dot{q} \quad \text{with} \quad \dot{q}_d = -K \left(\frac{\partial H}{\partial q} \right)^T, \quad K > 0$$

$$\dot{H} = \underbrace{\frac{\partial H}{\partial q} J^\dagger(q) v}_{\text{non si sa}} + \underbrace{-K \frac{\partial H}{\partial q} (I - J^\dagger J) \left(\frac{\partial H}{\partial q} \right)^T}_{<0}$$

- Max dist. obstacles:** $H = \min_{p,o} \|p(q) - o\| \rightsquigarrow H \uparrow$
- Max dist. joint limit:** $H(q) = -\frac{1}{2n} \sum_{i=1}^n \left(\frac{q_i - \bar{q}_i}{q_{iM} - q_{im}} \right)^2 \rightsquigarrow H \downarrow$
- Max dist. from singularities:** $H(q) = \sqrt{\det(J(q) J^T(q))} \rightsquigarrow H \uparrow$

3. Statics

$$\tau^T \delta q = F^T \delta p \implies \text{🔧: } \tau = -J^T(q) F$$

$$\mathcal{N}(J) \equiv \mathcal{R}^\perp(J^T) \quad \mathcal{R}(J) \equiv \mathcal{N}^\perp(J^T)$$

Ellipsoids:

$$\|\dot{q}\|^2 = 1 \iff \dot{q}^T \dot{q} = 1 \xrightarrow{\dot{q} = J^\dagger v} v^T (J J^T)^{-1} v = 1 \implies E_v = \{v : v^T (J J^T)^{-1} v = 1\}$$

$$\|\dot{\tau}\|^2 = 1 \iff \tau^T \tau = 1 \xrightarrow{\tau = J^T F} E_F = \{F : F^T (J J^T) F = 1\}$$

Manipulability measure:

$$w(q) = \sqrt{\det(J J^T)} = |\lambda_1 \lambda_2 \cdots \lambda_n| = |\det(J)|$$

4. Dynamics

$$\mathcal{L} = \mathcal{T} - \mathcal{U} \quad (= \mathcal{K} - \mathcal{P}) \quad \frac{d}{dt} \left(\frac{\partial \mathcal{L}}{\partial \dot{q}_i} \right) - \frac{\partial \mathcal{L}}{\partial q_i} = \mathcal{F}_i \quad i = 1, \dots, n$$

Kinetic:

$$\mathcal{T} = \sum_{i=1}^n \mathcal{T}_i + \mathcal{T}_{m_i} \implies \mathcal{T} = \frac{1}{2} \sum_{i=1}^n \sum_{j=1}^n b_{ij}(q) \dot{q}_i \dot{q}_j = \frac{1}{2} \dot{q}^T B(q) \dot{q}$$

$$\begin{cases} \mathcal{T}_i = \frac{1}{2} m_i \dot{p}_i^T \dot{p}_i + \frac{1}{2} \omega_i^T {}^b R_i {}^i I_i ({}^b R_i)^T \omega_i \\ \mathcal{T}_{m_i} = \frac{1}{2} m_{m_i} \dot{p}_i^T \dot{p}_i + \frac{1}{2} \omega_i^T {}^b R_i {}^i I_{m_i} ({}^b R_i)^T \omega_i \end{cases}$$

$$\begin{cases} \mathcal{T}_i = \frac{1}{2} m_i \left(\dot{q}^T J_p^{(l_i)T} \right) \left(J_p^{(l_i)} \dot{q} \right) + \frac{1}{2} \left(\dot{q}^T J_o^{(l_i)T} \right) ({}^b R_i {}^i I_i ({}^b R_i)^T) \left(J_o^{(l_i)} \dot{q} \right) \\ \mathcal{T}_{m_i} = \frac{1}{2} m_{m_i} \left(\dot{q}^T J_p^{(m_i)T} \right) \left(J_p^{(m_i)} \dot{q} \right) + \frac{1}{2} \left(\dot{q}^T J_o^{(m_i)T} \right) ({}^b R_{m_i} {}^{m_i} I_{m_i} ({}^b R_{m_i})^T) \left(J_o^{(m_i)} \dot{q} \right) \end{cases}$$

Potential:

$$\mathcal{U} = \sum_{i=1}^n \mathcal{U}_{l_i} + \mathcal{U}_{m_i} \implies \mathcal{U} = - \sum_{i=1}^n m_{l_i} g_0^T p_{l_i} + m_{m_i} g_0^T p_{m_i}$$

Dynamic equations:

$$\sum_{j=1}^n B_{ij}(q) \ddot{q}_j + \sum_{j=1}^n \sum_{k=1}^n h_{ijk}(q) \dot{q}_k \dot{q}_j + g_i(q) = \mathcal{F}_i \quad h_{ijk} = \frac{\partial B_{ij}}{\partial q_k} - \frac{1}{2} \frac{\partial B_{jk}}{\partial q_i}$$

$$g_i(q) = \frac{\partial \mathcal{U}}{\partial q_i} = - \sum_{j=1}^n m_{l_j} g_0^T J_{p_i}^{(l_j)}(q) + m_{m_j} g_0^T J_{p_i}^{(m_j)}(q)$$

$$B(q) \ddot{q} + C(q, \dot{q}) q + g(q) = \mathcal{F}$$

$$\Downarrow$$
$$B(q) \ddot{q} + C(q, \dot{q}) q + F_{viscous} \dot{q} + F_{static} \text{sgn}(\dot{q}) + g(q) = \tau - J^T(q) h$$

5. Trajectories

5.1 PTP

minimize

$$\int_0^{t_f} \boldsymbol{\tau}^2(t)dt$$

subject to

$$\int_0^{t_f} \boldsymbol{\omega}(t)dt = \mathbf{q}_f - \mathbf{q}_i \qquad (\tau = I\dot{\omega})$$

$$\begin{cases} \mathbf{q}(t) &= a_3t^3 + a_2t^2 + a_1t + a_0 \\ \dot{\mathbf{q}}(t) &= 3a_3t^2 + 2a_2t + a_1 \\ \ddot{\mathbf{q}}(t) &= 6a_3t + 2a_2 \end{cases}$$

$$\begin{cases} \mathbf{q}(t_i) = a_3t_i^3 + a_2t_i^2 + a_1t_i + a_0 \\ \mathbf{q}(t_f) = a_3t_f^3 + a_2t_f^2 + a_1t_f + a_0 \\ \dot{\mathbf{q}}(t_i) = 3a_3t_i^2 + 2a_2t_i + a_1 \\ \dot{\mathbf{q}}(t_i) = 3a_3t_f^2 + 2a_2t_f + a_1 \\ \mathbf{q}(t_i) = \mathbf{q}_i \\ \mathbf{q}(t_f) = \mathbf{q}_f \\ \dot{\mathbf{q}}(t_f) = \dot{\mathbf{q}}_i \\ \dot{\mathbf{q}}(t_f) = \dot{\mathbf{q}}_f \end{cases} \xrightarrow{t_f=0} \begin{cases} \mathbf{q}_i = a_0 \\ \mathbf{q}_f = a_3t_f^3 + a_2t_f^2 + a_1t_f + a_0 \\ \dot{\mathbf{q}}_i = a_1 \\ \dot{\mathbf{q}}_f = 3a_3t_f^2 + 2a_2t_f + a_1 \end{cases}$$

5.2 2-1-2

$$\left[\dot{\mathbf{q}}_c = \frac{\mathbf{q}_m - \mathbf{q}_c}{t_m - t_c} = \frac{\text{rise}}{\text{run}} \qquad \ddot{\mathbf{q}}t_c = \dot{\mathbf{q}} = \frac{\mathbf{q}_m - \mathbf{q}_c}{t_m - t_c} \qquad \ddot{\mathbf{q}}_ct_c^2 + \ddot{\mathbf{q}}_ct_ft_c + \mathbf{q}_f - \mathbf{q}_i = 0\right]$$

$$t_c = \frac{t_f}{2} - \frac{1}{2}\sqrt{\frac{t_f^2\ddot{\mathbf{q}} - 4(\mathbf{q}_f - \mathbf{q}_i)}{\ddot{\mathbf{q}}_c}} \qquad \text{sgn}(\ddot{\mathbf{q}}) = \text{sgn}(\mathbf{q}_f - \mathbf{q}_i) \qquad |\ddot{\mathbf{q}}| \geq \frac{4|\mathbf{q}_f - \mathbf{q}_i|}{t_f^2}$$

$$\mathbf{q}(t) = \begin{cases} \mathbf{q}_i + \frac{1}{2}\ddot{\mathbf{q}}_ct^2 & 0 \leq t \leq t_c \\ \mathbf{q}_i + \ddot{\mathbf{q}}_ct_c(t - t_c/2) & t_c < t \leq t_f - t_c \\ \mathbf{q}_f - \frac{1}{2}\ddot{\mathbf{q}}_c(t_f - t)^2 & t_f - t_c < t \leq t_f \end{cases}$$

Assegnazione di $\dot{\mathbf{q}}_c$ invece di $\ddot{\mathbf{q}}_c$

$$\frac{|\mathbf{q}_f - \mathbf{q}_i|}{t_f} < |\dot{\mathbf{q}}_c| \leq 2\frac{|\mathbf{q}_f - \mathbf{q}_i|}{t_f} \qquad t_c = \frac{\mathbf{q}_i - \mathbf{q}_f + \dot{\mathbf{q}}_ct_f}{\dot{\mathbf{q}}_c} \qquad \ddot{\mathbf{q}} = \frac{\dot{\mathbf{q}}_c^2}{\mathbf{q}_i - \mathbf{q}_f + \dot{\mathbf{q}}t_f}$$

5.3 Operational space

$$x_{traj} = \begin{bmatrix} p(t) \\ \phi(t) \end{bmatrix} \qquad \dot{p} = \dot{s}\frac{dp}{ds} = \dot{s}t \qquad ; \qquad \mathbf{t} = \frac{d\mathbf{p}}{ds} \qquad \mathbf{n} = \frac{\frac{d^2\mathbf{p}}{ds^2}}{\|\frac{d^2\mathbf{p}}{ds^2}\|} \qquad \mathbf{b} = \mathbf{t} \times \mathbf{n}$$

5.3.1 Segment

$$p(s) = p_i + \frac{s(p_f - p_i)}{\|p_f - p_i\|} \qquad t = \frac{dp}{ds} = \frac{(p_f - p_i)}{\|p_f - p_i\|} \qquad \frac{d^2p}{ds^2} = 0$$

$$p(s) = p_i + \frac{s(p_f - p_i)}{\|p_f - p_i\|} \qquad \dot{p} = \frac{\dot{s}(p_f - p_i)}{\|p_f - p_i\|} = \dot{s}t \qquad \ddot{p} = \frac{\ddot{s}(p_f - p_i)}{\|p_f - p_i\|} = \ddot{s}t$$

5.3.2 Circonference

$$p'(s) = \begin{bmatrix} \rho \cos(\frac{s}{\rho}) & \rho \sin(\frac{s}{\rho}) & 0 \end{bmatrix} \implies p(s) = c + {}^{\mathcal{O}}R_{\mathcal{O}}p'(s)$$

$$\frac{dp}{ds} = R \begin{bmatrix} -\sin(s/\rho) & \cos(s/\rho) & 0 \end{bmatrix} \qquad \frac{d^2p}{ds^2} = R \begin{bmatrix} -\cos(s/\rho)/\rho & -\sin(s/\rho)/\rho & 0 \end{bmatrix}$$

$$p(s) = c + R \begin{bmatrix} \rho \cos(s/\rho) \\ \rho \sin(s/\rho) \\ 0 \end{bmatrix} \qquad \dot{p} = R \begin{bmatrix} -\dot{s} \sin(s/\rho) \\ \dot{s} \sin(s/\rho) \\ 0 \end{bmatrix} \qquad \ddot{p} = R \begin{bmatrix} -\dot{s}^2\rho^{-1} \cos(s/\rho) - \ddot{s} \sin(s/\rho) \\ -\dot{s}^2\rho^{-1} \sin(s/\rho) + \ddot{s} \sin(s/\rho) \\ 0 \end{bmatrix}$$

5.3.3 Attitude trajectory

$$\phi(s) = \phi_i + \frac{s(\phi_f - \phi_i)}{\|\phi_f - \phi_i\|} \qquad \dot{\phi} = \frac{\dot{s}(\phi_f - \phi_i)}{\|\phi_f - \phi_i\|} \qquad \ddot{\phi} = \frac{\ddot{s}(\phi_f - \phi_i)}{\|\phi_f - \phi_i\|}$$

6. Control

6.1 Actuator model

mech: $K_r^{-1}\tau = K_t i_a$

electr: $v_a = R_a i_a + K_v \dot{q}_m$, $v_a = G_v V_c$

$[K_rq = q_m]$

6.1.1 Velocity generator:

$$\omega_m = \frac{G_v}{k_v}v'_c \qquad F = F_vK_rK_tR_a^{-1}K_vK_r \qquad u = K_rK_tR_a^{-1}G_vv_c$$

$$u = \tau + F\dot{q} \implies \tau = K_rK_tR_a^{-1}(G_vv_c - K_vK_r\dot{q}) \qquad v_c \approx G_v^{-1}K_vK_r\dot{q}$$

6.1.2 Torque generator:

$$c_m \approx \frac{k_t}{k_i}(v'_c - \frac{k_v}{G_v}\omega_m)$$

6.2 Decentralized joint control

$$\tau = K_r\tau_m \qquad q = K_r^{-1}q_m \qquad B(q) = \bar{B} + \Delta B(q)$$

$$K_r^{-1}\bar{B}K_r^{-1}\ddot{q}_m + \underbrace{K_r^{-1}\Delta B(q)K_r^{-1}\ddot{q}_m + K_r^{-1}C(q,\dot{q})K_r^{-1}\dot{q}_m + K_r^{-1}g(q)}_d + \underbrace{K_r^{-1}F_vK_r^{-1}}_{F_m}\dot{q}_m = \tau_m$$

$$\textbf{t.f. motor: } M(s) = \frac{k_m}{s(1 + T_ms)} \qquad k_m = \frac{1}{k_v} \text{ , } T_m = \frac{R_aI}{k_tk_v}$$

$$\textbf{PI control: } C(s) = K_c\frac{1 + sT_c}{s} \qquad [\text{ } K_c \equiv K_p, T_c \equiv T_p \parallel K_c \equiv K_v, \dots]$$

6.2.1 Position feedback

forward path:

$$G(s) = \frac{k_mK_p(1 + sT_p)}{s^2(1 + sT_m)} \implies \begin{cases} \times & T_p < T_m \\ \checkmark & T_p > T_m \\ \checkmark \frown & T_p \gg T_m \end{cases}$$

6.3 Centralized joint control

current controlled $\implies i_a = G_iv_c \implies u = K_rK_tG_iv_c = \tau$

$$x = \begin{bmatrix} q \\ \dot{q} \end{bmatrix} \implies \dot{x} = \begin{bmatrix} \dot{q} \\ B^{-1}(q)[u - C(q,\dot{q})\dot{q} - F\dot{q} - g(q)] \end{bmatrix} \qquad x_{eq} \iff \dot{x} = 0 \iff \begin{cases} \dot{q} = 0 \\ \bar{u} = g(\bar{q}) \end{cases}$$

6.3.1 PD control with gravity compensation

$$V(\dot{q},e) = \frac{1}{2}\dot{q}^TB(q)\dot{q} + \frac{1}{2}e^TK_Pe > 0 \qquad \forall \dot{q}, e \neq 0 \qquad e \triangleq q_d - q$$

$$\dot{V} = \dot{q}^TB(q)\ddot{q} + \frac{1}{2}\dot{q}^T\dot{B}(q)\dot{q} - \dot{q}^TK_Pe \qquad u = g(q) + K_Pe - K_d\dot{q}$$

6.3.2 Inverse dynamics (feedback linearization)

$$B(q)\ddot{q} + n(q,\dot{q}) = \tau = u \xrightarrow{F.L.} u \triangleq B(q)y + n(q,\dot{q}) \implies \ddot{q} = y$$

PD control: $y \triangleq -K_Pq - K_D\dot{q} + r$, $r \triangleq \ddot{q}_d + K_Pq_d + K_D\dot{q}_d$

$$\left[\begin{array}{c} \ddot{q}=y \\ \ddot{q} + K_Pq + K_D\dot{q} = r \end{array} \implies \ddot{e} + K_De + K_Pe = 0 \right]$$

$$\implies \mathbf{y} = \mathbf{K_p}(q_d - \mathbf{q}) + \mathbf{K_d}(\dot{q}_d - \dot{\mathbf{q}}) + \ddot{\mathbf{q}}_d$$

$$\left[\begin{array}{cc} K_P = diag\{\omega_{n1}^2, \dots, \omega_{nn}^2\} & K_D = diag\{2\zeta\omega_{n1}, \dots, 2\zeta\omega_{nn}^2\} \end{array} \right]$$

6.4 Operational space control

6.4.1 PD with gravity compensation

$$e \triangleq x_d - x \qquad u = g(q) + J_A^T(q)K_Pe - J_A^T(q)K_PK_DJ_A(q)\dot{q}$$

$$V(\dot{q},e) = \frac{1}{2}\dot{q}^TB(q)\dot{q} + \frac{1}{2}e^TK_Pe > 0 \qquad \forall \dot{q}, e \neq 0$$

at equilibrium $\dot{x} = (\dot{q},\ddot{q}) = 0 \implies -J_A^T(q)K_Pe = 0$

6.4.2 Inverse dynamics (feedback linearization)

$$\dot{x} = J_A(q)\dot{q} \implies \ddot{x} = \dot{J}_A(q)\dot{q} + \dot{J}_A(q,\dot{q})\dot{q}$$

$$u \triangleq B(q)y + n(q,\dot{q}) \implies \ddot{q} = y \implies y \triangleq J_A^{-1}(q)(\ddot{x}_d + K_De + K_Pe - \dot{J}_A(q,\dot{q})\dot{q})$$

7. Control of the interaction

$$B(q)\ddot{q} + n(q,\dot{q}) = u - \underbrace{J^T(q)h}_{interaction} \implies \text{PD with gravity comp. } J_A^T(q)K_Pe = J^T(q)h$$

$$h_A = T_A^T(x)KT_A(x)dx = K_A(x)(x - x_e) \implies e = K_P^{-1}K_A(x)(x - x_e)$$

$$x_\infty = (I - K_P^{-1}K_A(x))^{-1}(x_d + K_P^{-1}K_A(x)x_e) \qquad h_{A\infty} = (I + K_A(x)K_P^{-1})^{-1}K_A(x)(x_d - x_e)$$

8. Mobile Robotics

holonomic constr. (integrable)

$$\iff h_i(\mathbf{q}) = 0, \text{ } i = 1 \dots k < n \implies \begin{array}{l} \text{kin.} \\ \text{constr.} \end{array} : \frac{dh_i(\mathbf{q})}{dt} = \frac{dh_i(\mathbf{q})}{d\mathbf{q}}\dot{\mathbf{q}} = 0$$

kin. constr. $a_i(\mathbf{q},\dot{\mathbf{q}}) = 0 \implies \text{pfaffian } \mathbf{a}_i^T(\mathbf{q})\dot{\mathbf{q}} = 0 \leftrightarrow \mathbf{A}^T(\mathbf{q})\dot{\mathbf{q}} = 0$

$$\dot{\mathbf{q}} \in \mathcal{N}(\mathbf{A}^T(\mathbf{q})) \implies \langle \mathbf{g}_1(\mathbf{q}), \dots, \mathbf{g}_n - k(\mathbf{q}) \rangle \text{ base of } \mathcal{N} \implies \dot{\mathbf{q}} = \mathbf{G}(\mathbf{q})\mathbf{u}$$

8.1 Unicycle

pure rolling c.:

$$\frac{dy}{dx} = \tan \theta \implies \mathbf{q} = \begin{bmatrix} x \\ y \\ \theta \end{bmatrix} \implies \begin{bmatrix} \sin \theta \\ -\cos \theta \\ 0 \end{bmatrix}^T \dot{\mathbf{q}} = 0 \text{ , } \mathbf{G}(\mathbf{q}) = \begin{bmatrix} \cos \theta & 0 \\ \sin \theta & 0 \\ 0 & 1 \end{bmatrix}$$

8.2 Differential drive

$$v = \frac{r(\omega_R + \omega_L)}{2} \qquad \omega = \frac{r(\omega_R - \omega_L)}{d}$$

8.3 Bike

pure rolling (front w., back w.): $\dot{x}_f \sin(\theta + \phi) - \dot{y}_f \cos(\theta + \phi) = 0 \text{ , } \dot{x} \sin \theta - \dot{y} \cos \theta = 0$

$$x_f = x + L \cos \theta \text{ , } y_f = y + L \sin \theta \xrightarrow{1^{st}c.} \dot{x} \sin(\theta + \phi) - \dot{y} \cos(\theta + \phi) - L\dot{\theta} \cos \phi = 0$$

$$\mathbf{A}^T(\mathbf{q}) = \begin{bmatrix} \sin \theta & -\cos \theta & 0 & 0 \\ \sin(\theta + \phi) & -\cos(\theta + \phi) & -L \cos \phi & 0 \end{bmatrix} \qquad \mathbf{G}(\mathbf{q}) = \begin{bmatrix} \cos \theta \cos \phi & 0 \\ \sin \theta \cos \phi & 0 \\ \sin \phi / L & 0 \\ 0 & 1 \end{bmatrix}$$

$$\begin{bmatrix} \dot{x} \\ \dot{y} \\ \dot{\theta} \\ \dot{\phi} \end{bmatrix} = \mathbf{G}_1(\mathbf{q})u_1 + \mathbf{G}_2(\mathbf{q})u_2 \quad (u_2 \equiv \omega) \qquad \text{if front drive: } u_1 = v \text{ , if back d.: } u_1 = \frac{v}{\cos \phi}$$

$$R_x(\theta) = \begin{bmatrix} 1 & 0 & 0 \\ 0 & \cos \theta & -\sin \theta \\ 0 & \sin \theta & \cos \theta \end{bmatrix} \qquad R_y(\theta) = \begin{bmatrix} \cos \theta & 0 & \sin \theta \\ 0 & 1 & 0 \\ -\sin \theta & 0 & \cos \theta \end{bmatrix} \qquad R_z(\theta) = \begin{bmatrix} \cos \theta & -\sin \theta & 0 \\ \sin \theta & \cos \theta & 0 \\ 0 & 0 & 1 \end{bmatrix}$$