Skew symmetric matrix

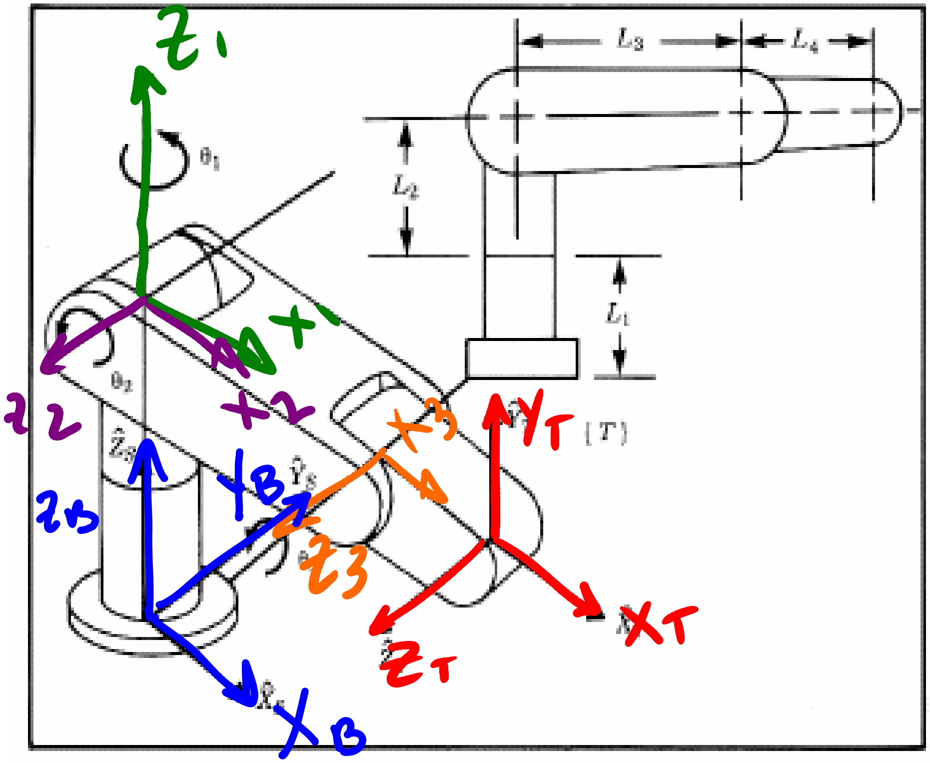
$$S = \begin{bmatrix} 0 & -\Omega_z & \Omega_y \\ \Omega_z & 0 & -\Omega_x \\ -\Omega_y & \Omega_x & 0 \end{bmatrix}$$

MECH 498: Introduction to Robotics

Inverse Manipulator Kinematics

M. O'Malley

Manipulator Kinematics – Example – 3R

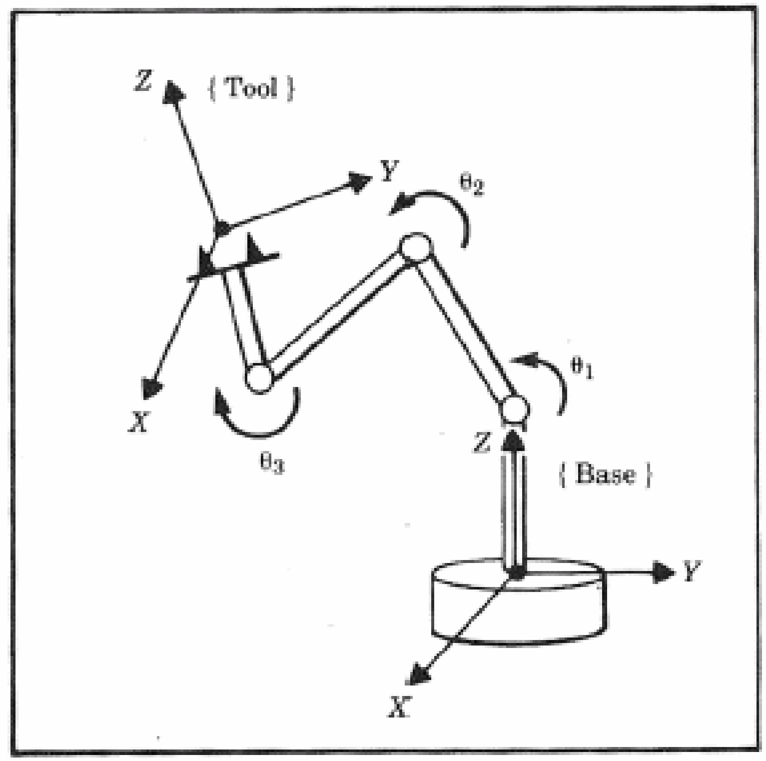


i-1	i	α_{i-1}	a_{i-1}	d_i	θ_i
0	1	0	0	$L_1 + L_2$	θ_1
1	2	90°	0	0	θ_2
2	3	0	L_3	0	θ_3
3	4 T	0	L_4	0	0

$$ {}^{B}_{T}T = {}^{0}_{4}T = {}^{0}_{1}T\,{}^{1}_{2}T\,{}^{2}_{3}T\,{}^{3}_{4}T $$

Direct vs. Inverse Kinematics

- **Direct (Forward) Kinematics**
  - Given: Joint angles and links geometry
  - Compute: Position and orientation of the end effector relative to the base frame



- **Inverse Kinematics**
  - Given: Position and orientation of the end effector relative to the base frame
  - Compute: All possible sets of joint angles and link geometries which could be used to attain the given position and orientation of the end effector

Solvability – PUMA 560

Given : PUMA 560 - 6 DOF, ${}^0_6T$

Solve: $\theta_1 \cdots \theta_6$

$$ {}^0_6T = {}^0_1T\,{}^1_2T\,{}^2_3T\,{}^3_4T\,{}^4_5T\,{}^5_6T = \begin{bmatrix} r_{11} & r_{12} & r_{13} & p_x \\ r_{21} & r_{22} & r_{23} & p_y \\ r_{31} & r_{32} & r_{33} & p_z \\ 0 & 0 & 0 & 1 \end{bmatrix} $$

$$ r_{11} = c_1[c_{23}(c_4c_5c_6 - s_4s_6) - s_{23}s_5c_6] + s_1(s_4c_5c_6 + c_4s_6), $$
$$ r_{21} = s_1[c_{23}(c_4c_5c_6 - s_4s_6) - s_{23}s_5c_6] - c_1(s_4c_5c_6 + c_4s_6), $$
$$ r_{31} = -s_{23}(c_4c_5c_6 - s_4s_6) - c_{23}s_5c_6, $$

$$ r_{12} = c_1[c_{23}(-c_4c_5s_6 - s_4c_6) + s_{23}s_5s_6] + s_1(c_4c_6 - s_4c_5s_6), $$
$$ r_{22} = s_1[c_{23}(-c_4c_5s_6 - s_4c_6) + s_{23}s_5s_6] - c_1(c_4c_6 - s_4c_5s_6), $$
$$ r_{32} = -s_{23}(-c_4c_5s_6 - s_4c_6) + c_{23}s_5s_6, $$

$$ r_{13} = -c_1(c_{23}c_4s_5 + s_{23}c_5) - s_1s_4s_5, $$
$$ r_{23} = -s_1(c_{23}c_4s_5 + s_{23}c_5) + c_1s_4s_5, $$
$$ r_{33} = s_{23}c_4s_5 - c_{23}c_5, $$

12 EQNS

$$ p_x = c_1[a_2c_2 + a_3c_{23} - d_4s_{23}] - d_3s_1, $$
$$ p_y = s_1[a_2c_2 + a_3c_{23} - d_4s_{23}] + d_3c_1, $$
$$ p_z = -a_3s_{23} - a_2s_2 - d_4c_{23}. $$

Total Number of Equations: 12

Independent Equations: 3 - Rotation Matrix

3 - Position Vector

Type of Equations: Non-linear

Solvability

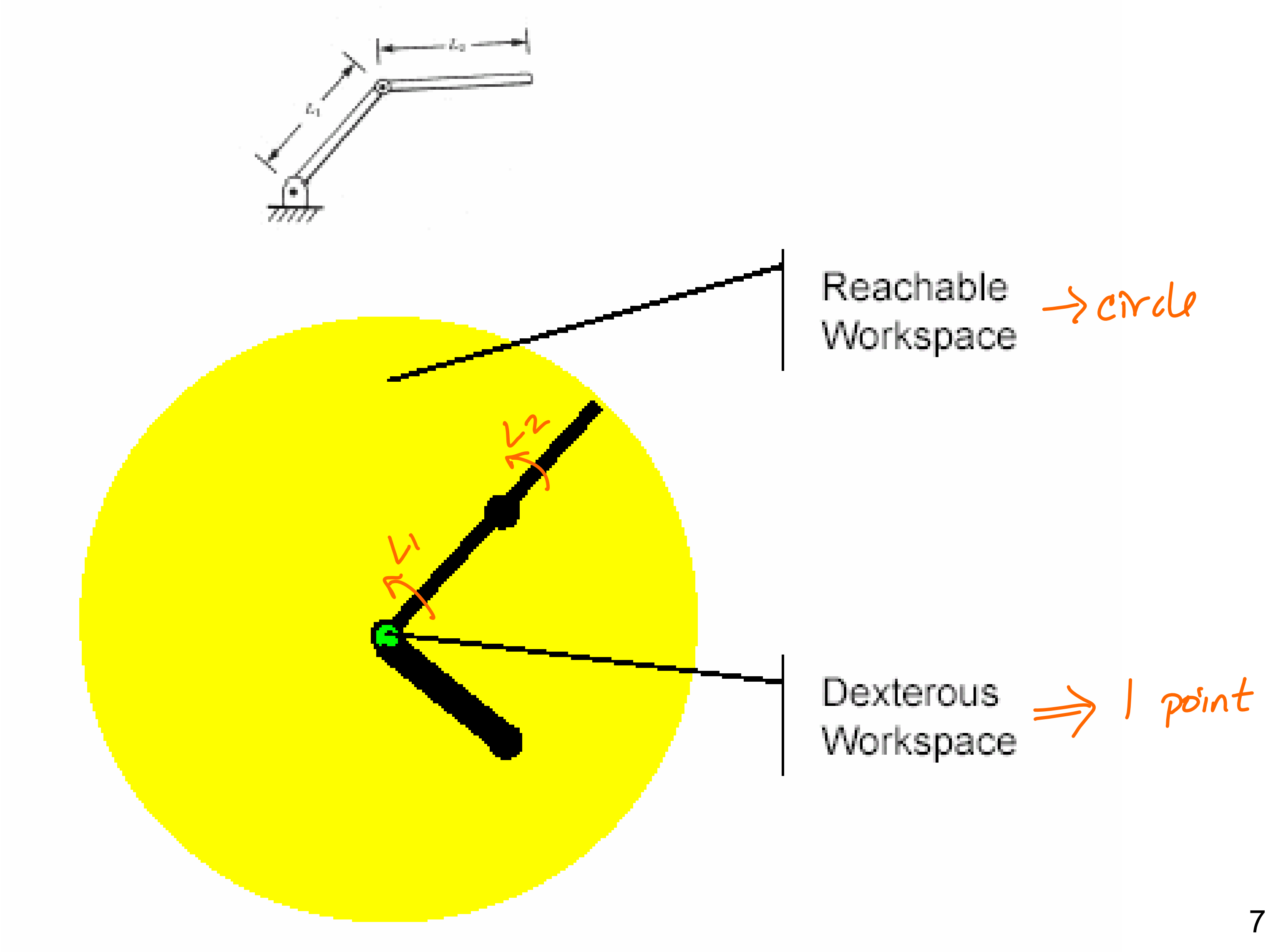
- **Existence of Solutions**
- **Multiple Solutions**
- **Method of solutions**
  - Closed form solution
    - Algebraic solution
    - Geometric solution
  - Numerical solutions

Solvability – Existence of Solution

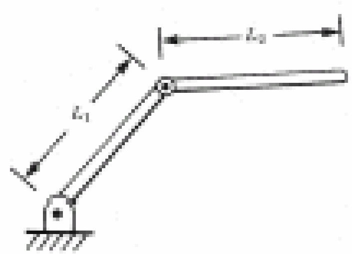
transformation to goal point

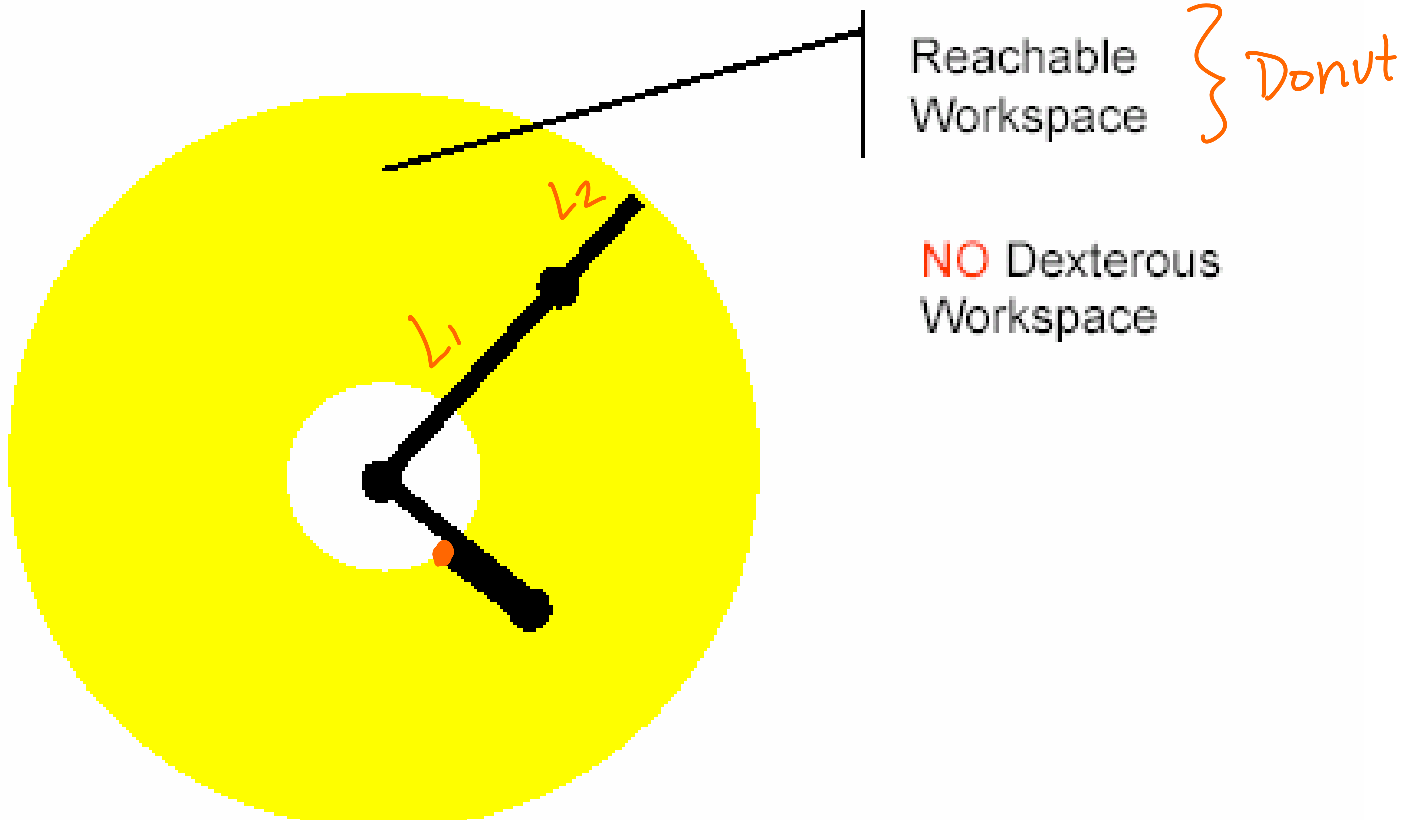
- For a solution to exist, ${}^{0}_{N}T$ must be in the ***workspace*** of the manipulator
- ***Workspace*** - Definitions
  - ***Dexterous Workspace (DW)***: The subset of space in which the robot end effector can reach ***in all orientations***.
  - ***Reachable Workspace (RW):*** The subset of space in which the robot end effector can reach in ***at least 1 orientation***
- The Dexterous Workspace is a subset of the Reachable Workspace $DW \subset RW$

Solvability - Existence of Solution - Workspace - 2R
Example 1 – $\mathbf{L_1 = L_2}$

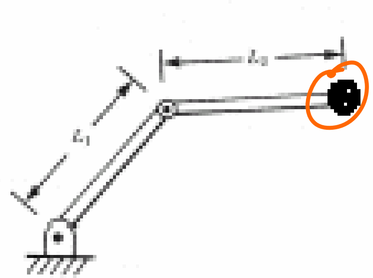


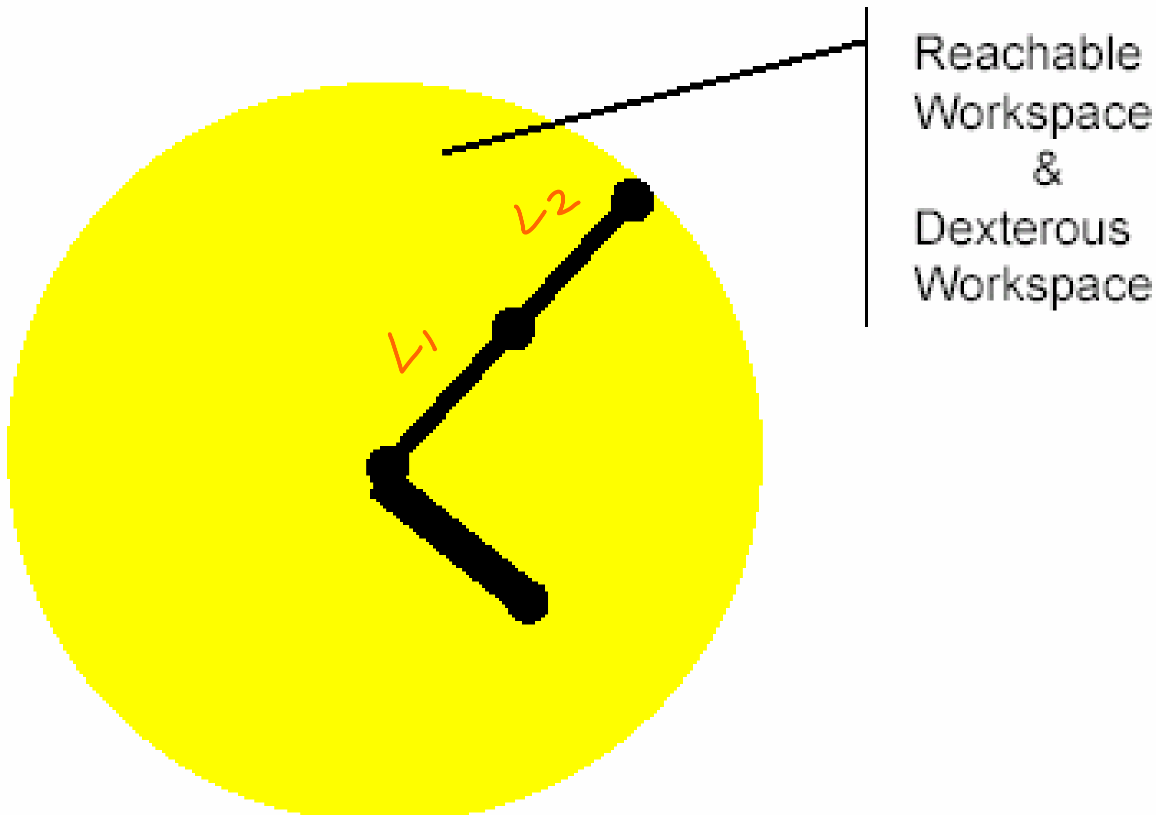
Solvability - Existence of Solution - Workspace - 2R
Example 2 – $L_1 \neq L_2$





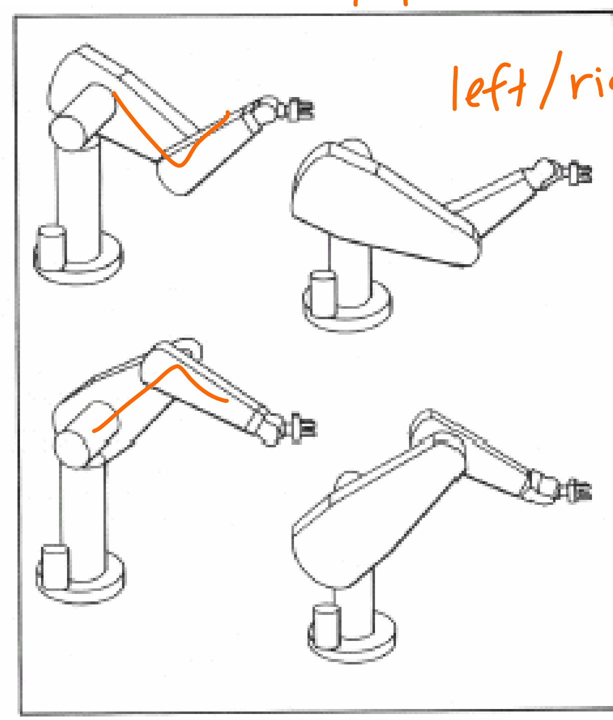
Solvability - Existence of Solution - Workspace - 3R
Example 3 – $\mathbf{L_1 = L_2}$





Solvability – Multiple Solutions

- Multiple solutions are a common problem that can occur when solving inverse kinematics because the system has to be able to chose one
- The number of solutions depends on the number of joints in the manipulator but is also a function of the link parameters *(a_i, α_i, θ_i, d_i)*
- Example: The PUMA 560 can reach certain goals with 8 different arm configurations (solutions)



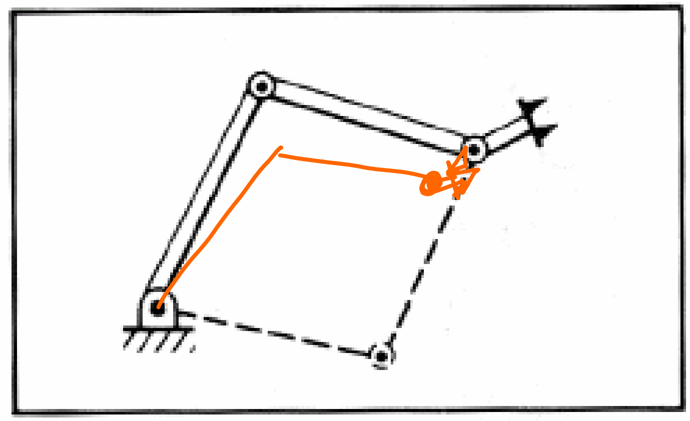
$$\theta_4' = \theta_4 + 180^o$$

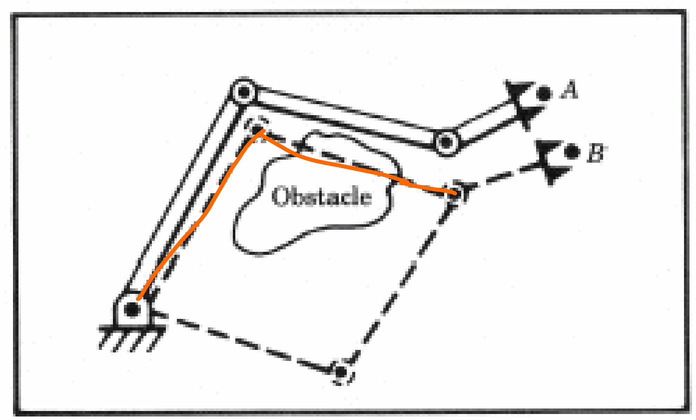
$$\theta_5' = -\theta_5$$

$$\theta_6' = \theta_6 + 180^o$$

Solvability – Multiple Solutions

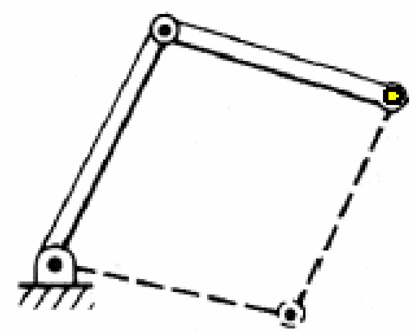
- **Problem:** The fact that a manipulator has multiple solutions may cause problems because the system has to be able to choose one
- **Solution:** Decision criteria
  - The closest (geometrically)
    - Minimizing the amount that each joint is required to move
    - Note 1: input argument - present position of the manipulator
    - Note 2: Joint Weight - Moving small joints (wrist) instead of moving large joints (Shoulder & Elbow)
  - Obstacles exist in the workspace
    - Avoiding collision



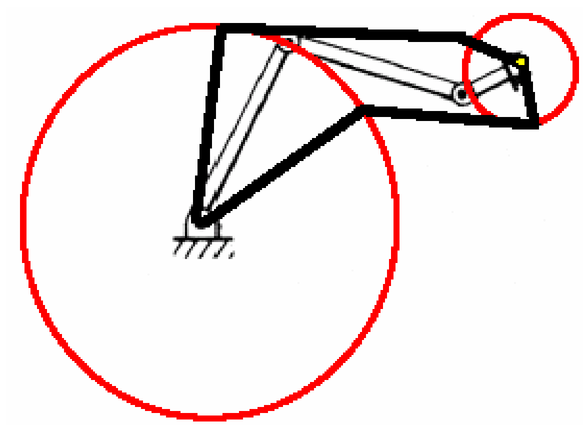


Solvability – Multiple Solutions – Number of Solutions

- Task Definition - Position the end effector in a specific point in the plane (2D)
- No. of DOF = No. of DOF of the task
  - Number of solutions:
    - 2 (elbow up/down)



- No. of DOF > No. of DOF of the task
  - Number of solutions: ∞
  - Self Motion - The robot can be moved without moving the end effector from the goal

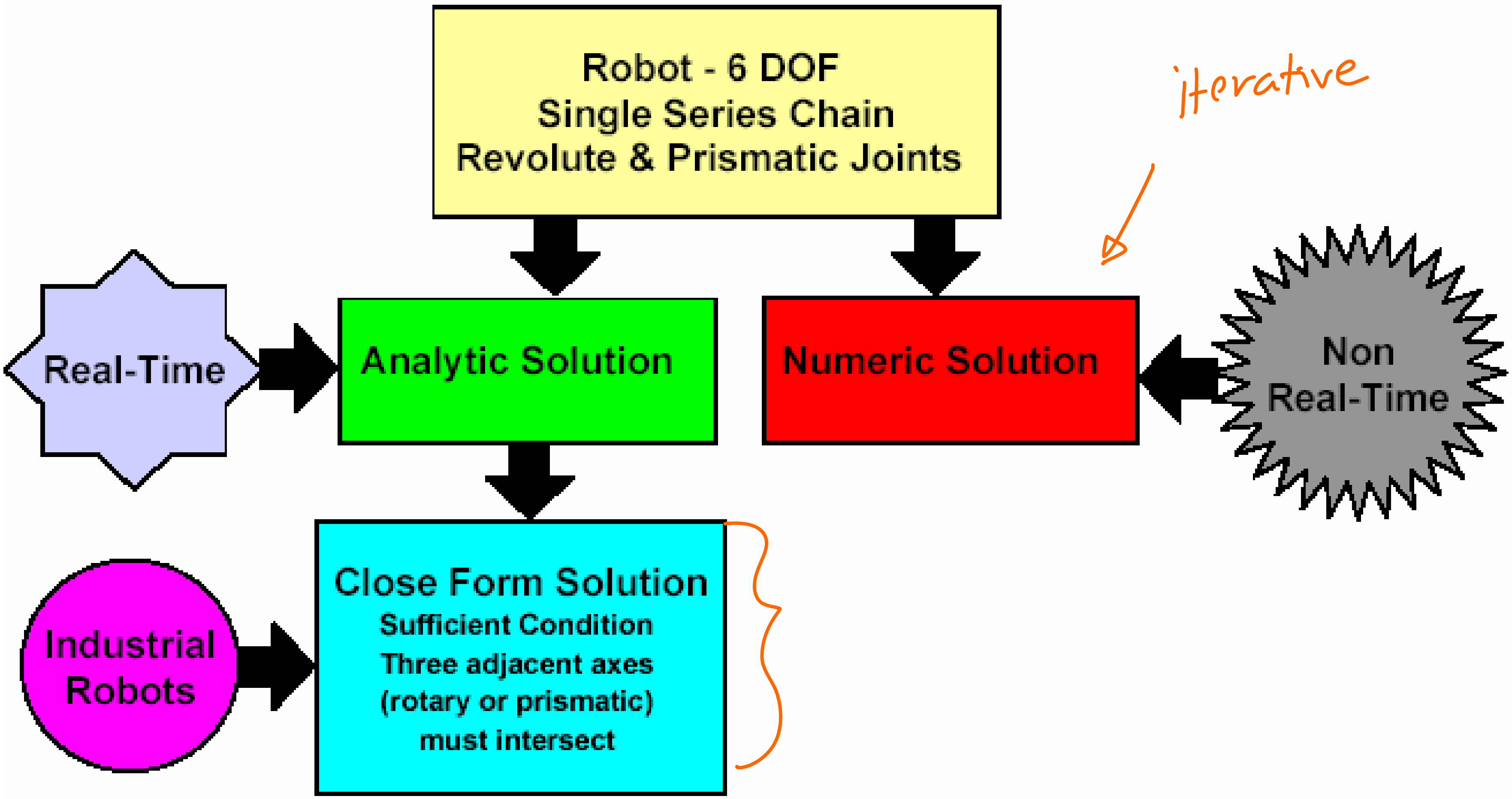


Solvability – Methods of Solutions

- **Solution** (Inverse Kinematics)- A “solution” is the set of joint variables associated with an end effector’s desired position and orientation.
- **No general algorithms** that lead to the solution of inverse kinematic equations.
- **Solution Strategies**
  – **Closed form Solutions** - An analytic expression includes all solution sets.
    - **Algebraic Solution** - Trigonometric (Nonlinear) equations
    - **Geometric Solution** - Reduces the larger problem to a series of plane geometry problems.

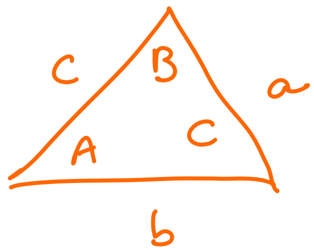
  – **Numerical Solutions** - Iterative solutions will not be considered in this course.

Solvability



Mathematical Equations

- Law of Sines / Cosines - For a general triangle



$$\frac{\sin A}{a} = \frac{\sin B}{b} = \frac{\sin C}{c}$$

$$a^2 = b^2 + c^2 - 2bc\cos A$$

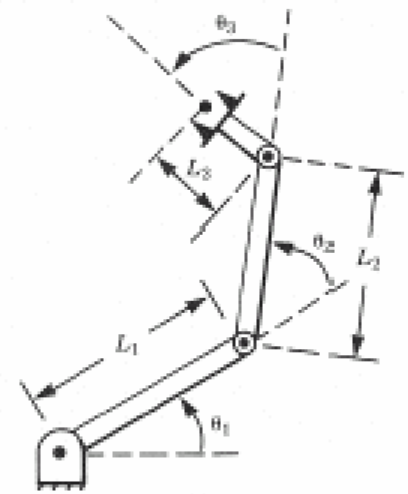
- Sum of Angles

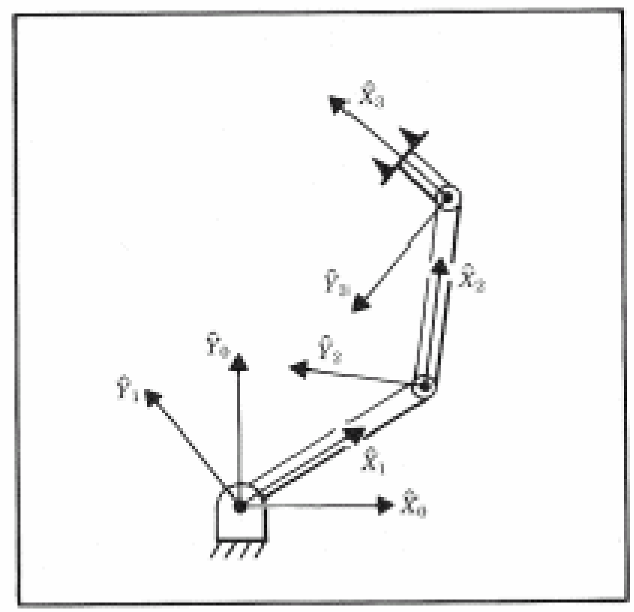
$$\sin(\theta_1 + \theta_2) = s_{12} = c_1 s_2 + s_1 c_2$$

$$\cos(\theta_1 + \theta_2) = c_{12} = c_1 c_2 - s_1 s_2$$

Inverse Kinematics - Planar RRR (3R) - Algebraic Solution

i	α_{i-1}	a_{i-1}	d_i	θ_i
1	0	0	0	θ_1
2	0	L_1	0	θ_2
3	0	L_2	0	θ_3





Inverse Kinematics - Planar RRR (3R) - Algebraic Solution

General Link Homogeneous Transformation

$$
{}^{i-1}_{\;i}T = \begin{bmatrix} c\theta_i & -s\theta_i & 0 & a_{i-1} \\ s\theta_i c\alpha_{i-1} & c\theta_i c\alpha_{i-1} & -s\alpha_{i-1} & -s\alpha_{i-1}d_i \\ s\theta_i s\alpha_{i-1} & c\theta_i s\alpha_{i-1} & c\alpha_{i-1} & c\alpha_{i-1}d \\ 0 & 0 & 0 & 1 \end{bmatrix}
$$

i	α_{i-1}	a_{i-1}	d_i	θ_i
1	0	0	0	θ_1
2	0	L_1	0	θ_2
3	0	L_2	0	θ_3

$$
{}^{0}_{1}T = \begin{bmatrix} c1 & -s1 & 0 & 0 \\ s1 & c1 & 0 & 0 \\ 0 & 0 & 1 & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix}
$$

$$
{}^{1}_{2}T = \begin{bmatrix} c2 & -s2 & 0 & L1 \\ s2 & c2 & 0 & 0 \\ 0 & 0 & 1 & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix}
$$

$$
{}^{2}_{3}T = \begin{bmatrix} c1 & -s3 & 0 & L2 \\ s3 & c3 & 0 & 0 \\ 0 & 0 & 1 & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix}
$$

Inverse Kinematics - Planar RRR (3R) - Algebraic Solution

Base → Wrist

$$ {}^{B}_{W}T = {}^{0}_{3}T = {}^{0}_{1}T\,{}^{1}_{2}T\,{}^{2}_{3}T = \begin{bmatrix} c1c2c3 - c1s2s3 - s1s2c3 - s1c2s3 & -c1c2s3 - c1s2c3 + s1s2s3 - s1c2c3 & 0 & c1(L2c2 + L1) - s1s2L2 \\ s1cc3 - s1s2s3 + c1s2c3 + c1c2s3 & -s1c2s3 - s1s2c3 - c1s2s3 + c1c2c3 & 0 & s1(L2c2 + L1) + c1s2L2 \\ 0 & 0 & 1 & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix} $$

- Using trigonometric identities to simplify ${}^{B}_{W}T$, the solution to the forward kinematics is:

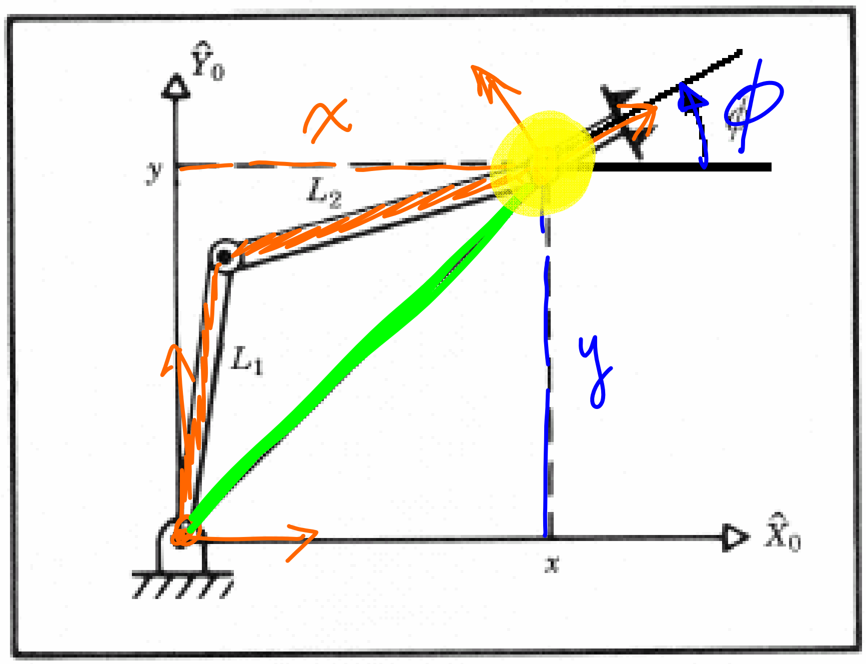
Forward Kinematics

$$ {}^{B}_{W}T = {}^{0}_{3}T = \begin{bmatrix} c_{123} & -s_{123} & 0 & \boxed{L_1c_1 + L_2c_{12}} \\ s_{123} & c_{123} & 0 & \boxed{L_1s_1 + L_2s_{12}} \\ 0 & 0 & 1 & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix} \begin{matrix} = x \\ = y \\ \\ \\ \end{matrix} $$

- **where** $c_{123} = \cos(\theta_1 + \theta_2 + \theta_3)$ $\quad s_{123} = \sin(\theta_1 + \theta_2 + \theta_3)$

Inverse Kinematics - Planar RRR (3R) - Algebraic Solution

- *Given:*
  - ***Direct Kinematics:*** *The homogenous transformation from the base to the wrist* ${}^B_W T$
  - ***Goal Point Definition*:** For a planar manipulator, specifying the goal can be accomplished by specifying three parameters: The position of the wrist in space (x, y) and the orientation of link 3 in the plane relative to the $\hat{X}$ axis (ϕ)



Inverse Kinematics - Planar RRR (3R) - Algebraic Solution

- ***Problem:***

What are the joint angles $(\theta_1, \theta_2, \theta_3)$ as a function of the wrist position and orientation (x, y, ϕ)

- ***Solution:***
- The goal in terms of position and orientation of the wrist expressed in terms of the homogeneous transformation is defined as follows

$$
{}^{B}_{W}T_{Goal} = \begin{bmatrix} c_\phi & -s_\phi & 0 & x \\ s_\phi & c_\phi & 0 & y \\ 0 & 0 & 1 & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix}
\qquad
{}^{B}_{W}T = {}^{0}_{3}T = \begin{bmatrix} c_{123} & -s_{123} & 0 & L_1c_1 + L_2c_{12} \\ s_{123} & c_{123} & 0 & L_1s_1 + L_2s_{12} \\ 0 & 0 & 1 & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix}
$$

Inverse Kinematics - Planar RRR (3R) - Algebraic Solution

$$ {}^{B}_{W}T_{Goal} = {}^{0}_{3}T $$

- A set of four nonlinear equations which must be solved for $\theta_1, \theta_2, \theta_3$

$$ c_\phi = c_{123} $$

$$ s_\phi = s_{123} $$

$$ x = l_1 c_1 + l_2 c_{12} $$

$$ y = l_1 s_1 + l_2 s_{12} $$

- Solving for θ_2
- If we square x and y add them while making use of $c_{12} = c_1 c_2 - s_1 s_2$;$s_{12} = c_1 s_2 + s_1 c_2$ we obtain

$$ x^2 + y^2 = l_1^2 + l_2^2 + 2 l_1 l_2 c_2 $$

Inverse Kinematics - Planar RRR (3R) - Algebraic Solution

- Solving for c_2 we obtain

$$c_2 = \frac{x^2 + y^2 - l_1^2 - l_2^2}{2 l_1 l_2}$$

- Note: In order for a solution to exist, the right hand side must have a value between -1 and 1. Physically if this constraints is not satisfied, then the goal point is too far away for the manipulator to re ıch.

reach

- Assuming the goal is in the workspace, and making use of $c_2^2 + s_2^2 = 1$ we write an expression for s_2 as

$$s_2 = \pm\sqrt{1 - c_2^{\,2}}$$

- Note: The choice of the sign corresponds to the multiple solutions in which we can choose the "elbow-up" or the "elbow-down" solution

Inverse Kinematics - Planar RRR (3R) - Algebraic Solution

- Solving for θ_1
- For solving θ_1 we rewrite the the original nonlinear equations using a **change of variables** as follows

$$\left.\begin{aligned} x &= l_1 c_1 + l_2 c_{12} \\ y &= l_1 s_1 + l_2 s_{12} \end{aligned}\right\} \text{Forward Kinematics}$$

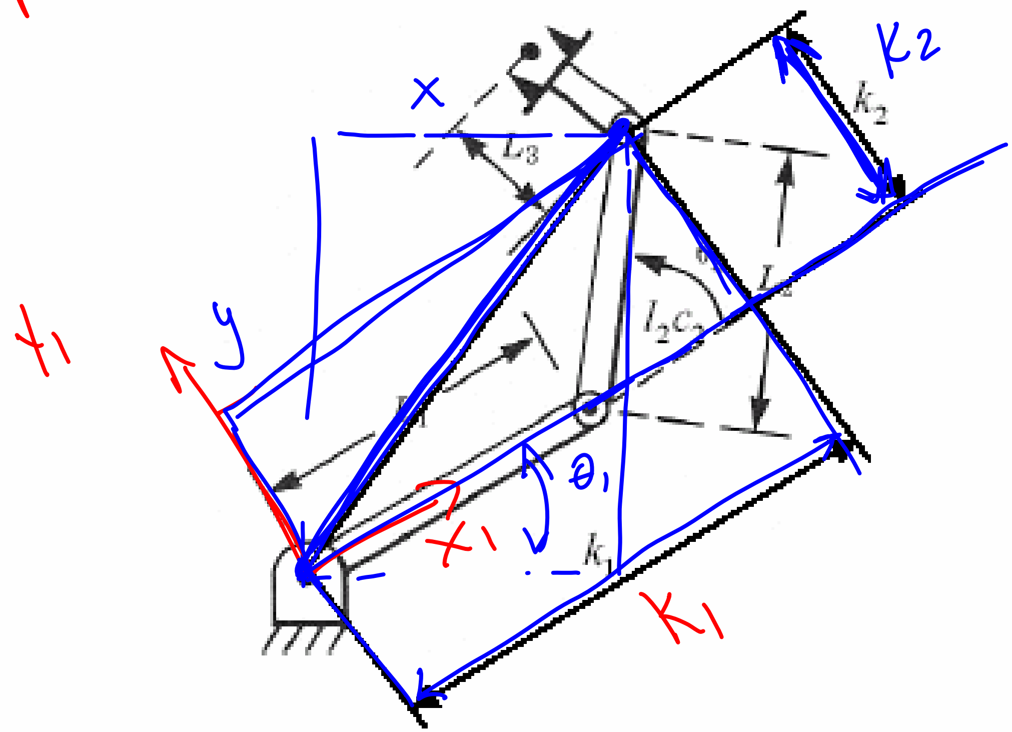
$$x = k_1 c_1 + k_2 s_1$$

$$y = k_1 s_1 + k_2 c_1$$

- where

$$k_1 = l_1 + l_2 c_2$$

$$k_2 = l_2 s_2$$



Inverse Kinematics - Planar RRR (3R) - Algebraic Solution

- Finally, we compute θ_2 using the two argument arctangent function

$$\theta_2 = \mathrm{Atan2}(\mathrm{s}_2, \mathrm{c}_2) = A\tan 2\left(\pm\sqrt{1 - c_2^2}, \frac{x^2 + y^2 - l_1^2 - l_2^2}{2 l_1 l_2}\right)$$

(2 slides back)

Inverse Kinematics - Planar RRR (3R) - Algebraic Solution

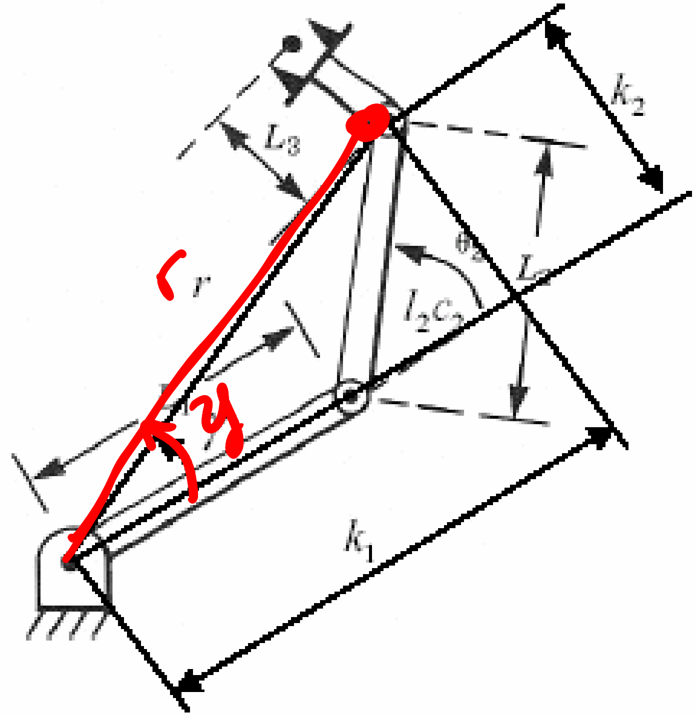
- Changing the way in which we write the constants k_1 and k_2

$$r = +\sqrt{k_1^2 + k_2^2}$$

$$\gamma = A\tan 2(k_2, k_1)$$ Angle from $\hat{x}_1$ to r

- Then

$$\left.\begin{aligned} k_1 &= r\cos\gamma \\ k_2 &= r\sin\gamma \end{aligned}\right\}$$



Inverse Kinematics - Planar RRR (3R) - Algebraic Solution

- Based on the previous two transformations, the equations can be rewritten as:

$$\begin{cases} x = r\cos\gamma\cos\theta_1 - r\sin\gamma\sin\theta_1 \\ y = r\cos\gamma\sin\theta_1 + r\sin\gamma\cos\theta_1 \end{cases}$$

- or

divide by r

$$\frac{x}{r} = \cos\gamma\cos\theta_1 - \sin\gamma\sin\theta_1$$

$$\frac{y}{r} = \cos\gamma\sin\theta_1 + \sin\gamma\cos\theta_1$$

- or

$$\frac{x}{r} = \cos(\underline{\gamma + \theta_1})$$

Simplify

$$\frac{y}{r} = \sin(\gamma + \theta_1)$$

Inverse Kinematics - Planar RRR (3R) - Algebraic Solution

- Using the two argument arctangent we finally get a solution for θ_1

$$\gamma + \theta_1 = A\tan 2(\frac{y}{r}, \frac{x}{r}) = A\tan 2(y, x)$$

$$\theta_1 = A\tan 2(y, x) - A\tan 2(k_2, k_1)$$

$$k_1 = l_1 + l_2 c_2$$
$$k_2 = l_2 s_2$$

- Note:

(1) When a choice of a sign is made in the solution of θ_2 above, it will cause a sign change in k_2 thus affecting θ_1

(2) If $x = y = 0$ then the solution becomes undefined - in this case θ_1 is arbitrary

Inverse Kinematics - Planar RRR (3R) - Algebraic Solution

- Solving for θ_3

- Based on the original equations,

$$c_\phi = c_{123}$$

$$s_\phi = s_{123}$$

- We can solve for the sum of $\theta_1, \theta_2, \theta_3$

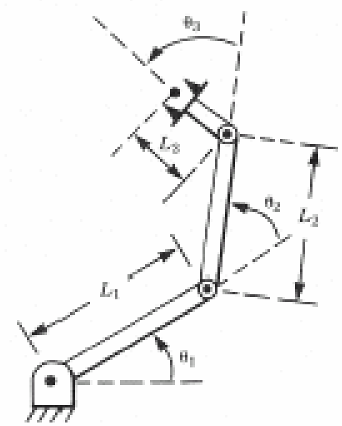
$$\theta_1 + \theta_2 + \theta_3 = A\tan 2(s_\phi, c_\phi) = \phi$$

$$\theta_3 = \phi - (\theta_1 + \theta_2)$$

- Note: It is typical with manipulators that have two or more links moving in a plane that in the course of a solution, expressions for sum of joint angles arise

Central Topic – Inverse Manipulator Kinematics - Examples

- ***Geometric Solution – Concept***
  - Decompose spatial geometry into several plane geometry problems
  - ***Examples*** - *Planar RRR (3R) manipulators* - Geometric Solution

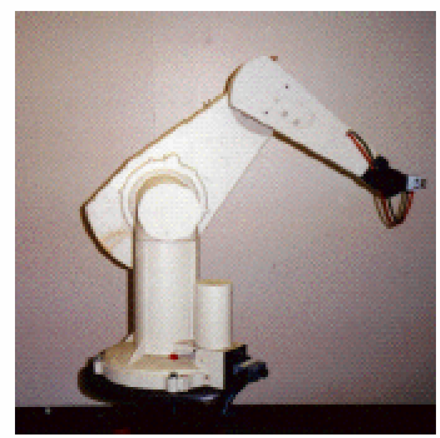


- ***Algebraic Solution - Concept***

$$
{}^{0}_{N}T = {}^{0}_{1}T \ldots {}^{N-1}_{N}T = \begin{bmatrix} r_{11} & r_{12} & r_{13} & p_x \\ r_{21} & r_{22} & r_{23} & p_y \\ r_{31} & r_{32} & r_{33} & p_z \\ 0 & 0 & 0 & 1 \end{bmatrix}
$$

Direct Kinematics   Goal (Numeric values)

  - ***Examples*** - *PUMA 560 - Algebraic Solution*

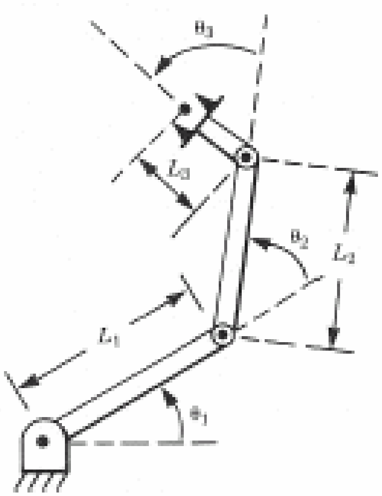


Inverse Kinematics - Planar RRR (3R) - Geometric Solution

- *Given:*
  - ***Manipulator Geometry***
  - ***Goal Point Definition***: The position x, y and orientation θ of the wrist in space

- *Problem:*

What are the joint angles ($\theta_1, \theta_2, \theta_3$) as a function of the goal (wrist position and orientation)



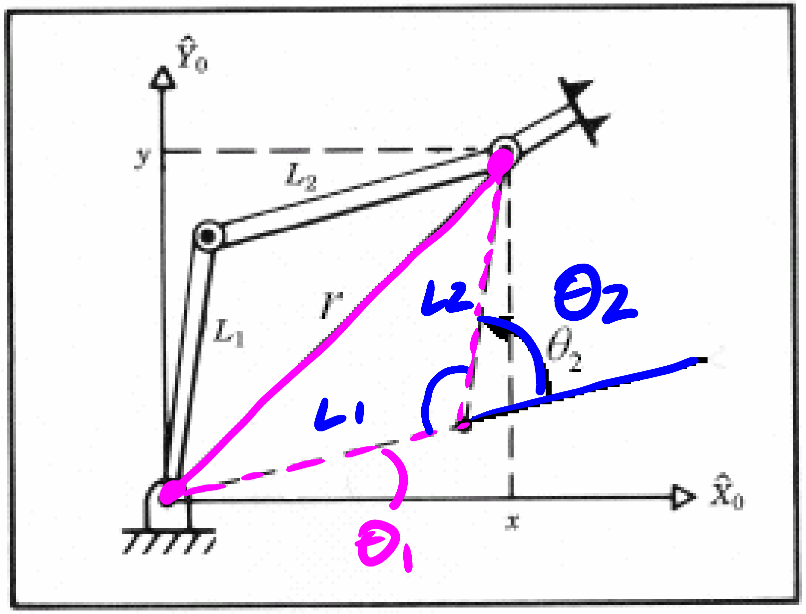
Inverse Kinematics - PUMA 560 - Geometric Solution

- *Solution:*

- We can apply the law of cosines to solve for θ_2

$$\underbrace{r^2 = x^2 + y^2}_{} = l_1^2 + l_2^2 - 2l_1 l_2 \cos(180 + \theta_2)$$

$180 - \theta_2$



- Since

$$\cos(180 + \theta_2) = -\cos\theta_2$$

- We have

$$c_2 = \frac{x^2 + y^2 - l_1^2 - l_2^2}{2l_1 l_2}$$

expression for θ_2

Inverse Kinematics - PUMA 560 - Geometric Solution

- Note : Condition - Should be checked by the computational algorithm to verify existence of solutions.

$$l_1 + l_2 \geq \sqrt{x^2 + y^2}$$

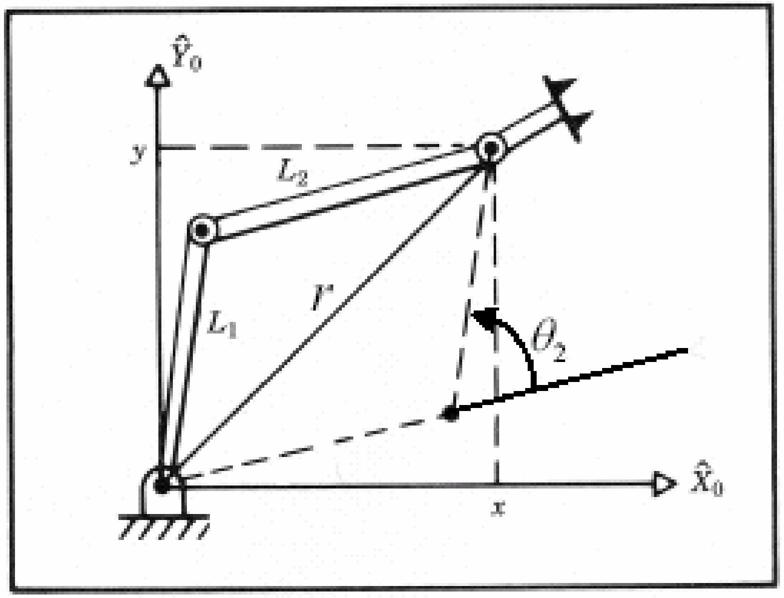
$\geq r$

- Assuming that the solution exist it lies in the range of

$$180^o \leq \theta_2 \leq 0^o$$

- The other possible solution may found by symmetry to be

$$\theta_2' = -\theta_2$$

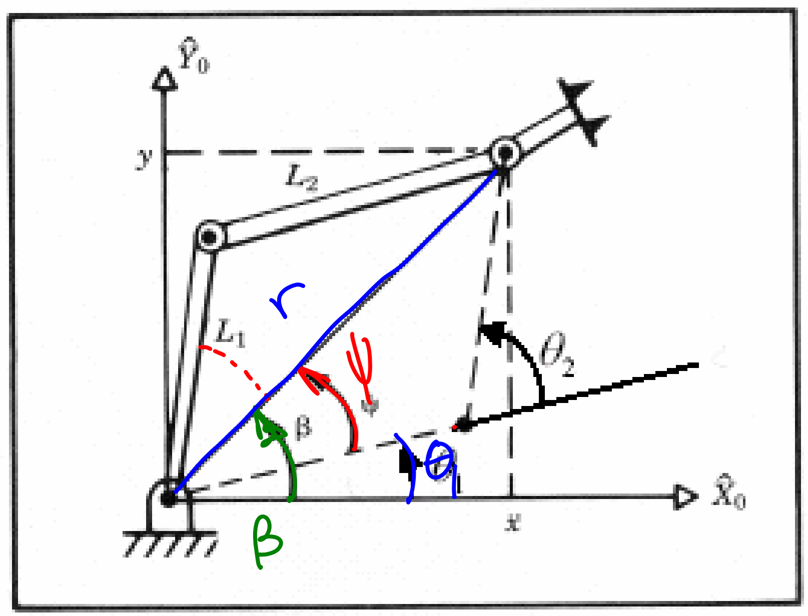


Inverse Kinematics - ~~PUMA 560~~ - Geometric Solution 3R

- By definition

$$\theta_1 = \beta \pm \psi \quad \begin{cases} \theta_2 < 0 \\ \theta_2 > 0 \end{cases}$$

$\psi \rightarrow x_1$ to r



- Defining β as a function of x,y

$$\beta = A\tan 2(y,x)$$

- Applying the law of cosine to find

$$\cos\psi = \frac{x^2 + y^2 + l_1^2 - l_2^2}{2l_1\sqrt{x^2 + y^2}}$$

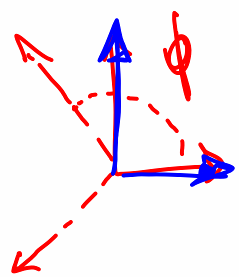
- Note: $0^0 \le \psi \le 180^o$

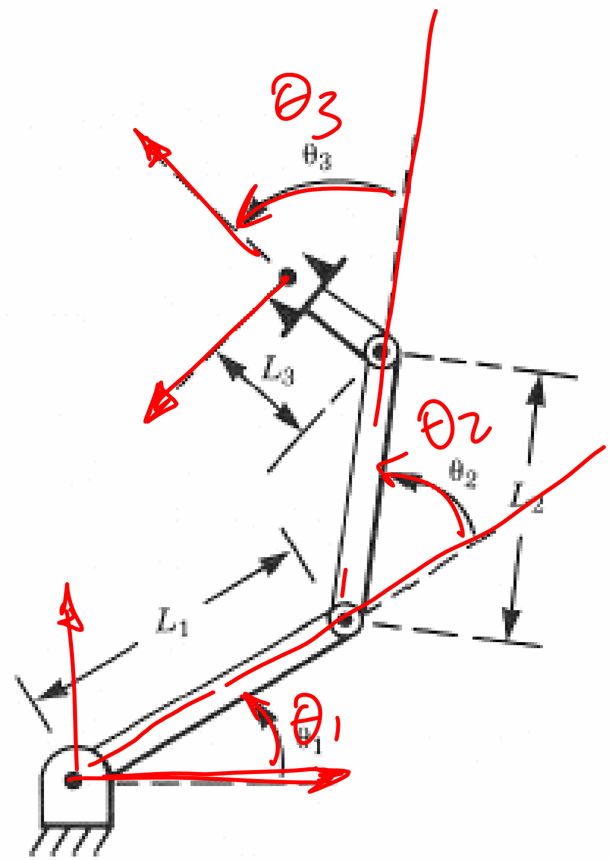
Inverse Kinematics - ~~PUMA 560~~ - Geometric Solution 3R

- Angle in the plane add up to define the orientation of the last link

$$\phi = \theta_1 + \theta_2 + \theta_3$$

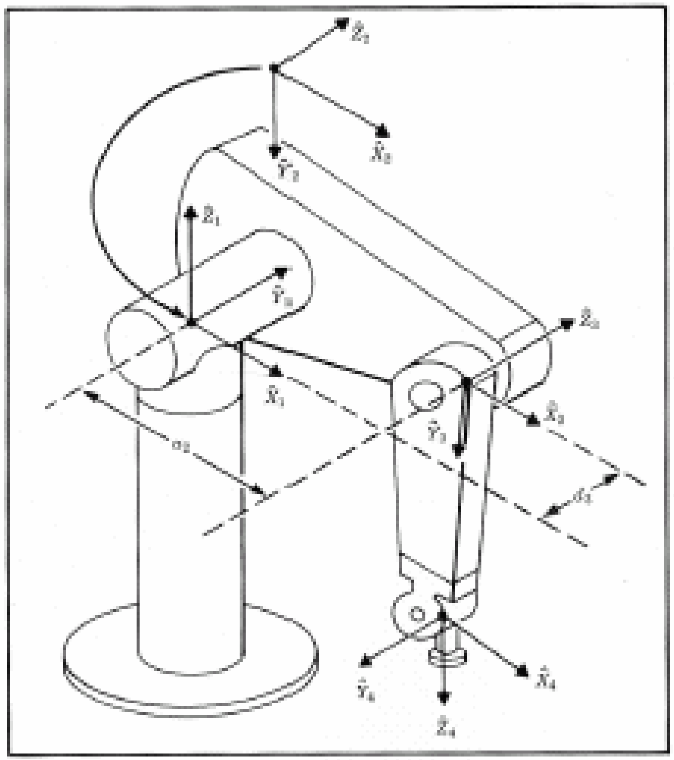
$$\theta_3 = \phi - \theta_1 + \theta_2$$

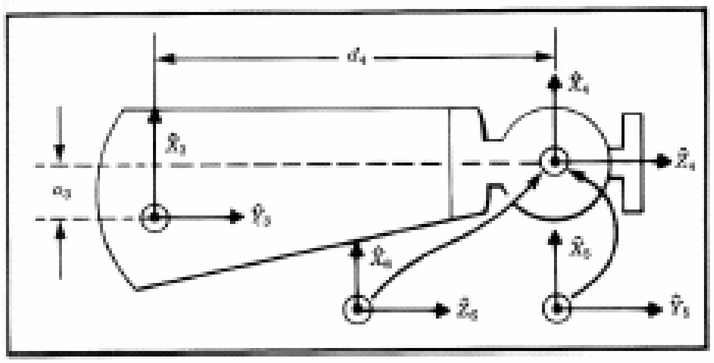




Inverse Kinematics - PUMA 560 - Algebraic Solution

- *Given:*
  - ***Direct Kinematics:*** *The homogenous transformation from the base to the wrist* ${}^{B}_{W}T$
  - ***Goal Point Definition***: The position and orientation of the wrist in space





Inverse Kinematics - PUMA 560 - Algebraic Solution

- ***Problem:***

What are the joint angles ($\theta_1 \cdots \theta_6$) as a function of the wrist position and orientation (or when ${}^0_6T$ is given as numeric values)

$$\underbrace{{}^0_6T = \overbrace{{}^0_1T(\theta_1)\ {}^1_2T(\theta_2)\ {}^2_3T(\theta_3)\ {}^3_4T(\theta_4)\ {}^4_5T(\theta_5)\ {}^5_6T(\theta_6)}^{}}_{\text{Direct Kinematics}} = \underbrace{\begin{bmatrix} r_{11} & r_{12} & r_{13} & p_x \\ r_{21} & r_{22} & r_{23} & p_y \\ r_{31} & r_{32} & r_{33} & p_z \\ 0 & 0 & 0 & 1 \end{bmatrix}}_{\text{Goal}}$$

Forward

Inverse Kinematics - PUMA 560 - Algebraic Solution

- ***Solution (General Technique):*** Multiplying each side of the direct kinematics equation by a an inverse transformation matrix for separating out variables in search of solvable equation

- Put the dependence on θ_1 on the left hand side of the equation by multiplying the direct kinematics eq. with $[{}^0_1T(\theta_1)]^{-1}$ gives

${}^0_1T^{-1}$ (func of θ_1)

$$[{}^0_1T(\theta_1)]^{-1}\ {}^0_6T = \underbrace{\boxed{[{}^0_1T(\theta_1)]^{-1}\ {}^0_1T(\theta_1)}}_{I}\ {}^1_2T(\theta_2)\ {}^2_3T(\theta_3)\ {}^3_4T(\theta_4)\ {}^4_5T(\theta_5)\ {}^5_6T(\theta_6)$$

$$[{}^0_3T(\theta_1,\theta_2,\theta_3)]^{-1}\ {}^0_6T = \boxed{[{}^0_3T(\theta_1)]^{-1}\ {}^0_1T(\theta_1)\ {}^1_2T(\theta_2)\ {}^2_3T(\theta_3)}\ {}^3_4T(\theta_4)\ {}^4_5T(\theta_5)\ {}^5_6T(\theta_6)$$

$$[{}^0_4T(\theta_1,\theta_2,\theta_3,\theta_4)]^{-1}\ {}^0_6T = \boxed{[{}^0_4T(\theta_1,\theta_2,\theta_3,\theta_4)]^{-1}\ {}^0_1T(\theta_1)\ {}^1_2T(\theta_2)\ {}^2_3T(\theta_3)\ {}^3_4T(\theta_4)}\ {}^4_5T(\theta_5)\ {}^5_6T(\theta_6)$$

$$[{}^0_5T(\theta_1,\theta_2,\theta_3,\theta_4,\theta_5)]^{-1}\ {}^0_6T = \boxed{[{}^0_5T(\theta_1,\theta_2,\theta_3,\theta_4,\theta_5)]^{-1}\ {}^0_1T(\theta_1)\ {}^1_2T(\theta_2)\ {}^2_3T(\theta_3)\ {}^3_4T(\theta_4)\ {}^4_5T(\theta_5)}\ {}^5_6T(\theta_6)$$

Inverse Kinematics - PUMA 560 - Algebraic Solution

- Put the dependence on θ_1 on the left hand side of the equation by multiplying the direct kinematics eq. with $[{}^0_1T(\theta_1)]^{-1}$ gives

$$[{}^0_1T(\theta_1)]^{-1}\ {}^0_6T = \underbrace{[{}^0_1T(\theta_1)]^{-1}\ {}^0_1T(\theta_1)}_{I}\ {}^1_2T(\theta_2)\ {}^2_3T(\theta_3)\ {}^3_4T(\theta_4)\ {}^4_5T(\theta_5)\ {}^5_6T(\theta_6)$$

$$ {}^0_1T = \begin{bmatrix} c\theta_1 & -s\theta_1 & 0 & 0 \\ s\theta_1 & c\theta_1 & 0 & 0 \\ 0 & 0 & 1 & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix} $$

$$ [{}^A_BT]^{-1} = {}^B_AT = \begin{bmatrix} \begin{bmatrix} & {}^A_BR^T & \end{bmatrix} & -{}^A_BR^T\,{}^AP_{BORG} \\ 0 \quad 0 \quad 0 & 1 \end{bmatrix} $$

(Refresher)

$$ {}^1_0T = [{}^0_1T]^{-1} = \begin{bmatrix} c\theta_1 & s\theta_1 & 0 & 0 \\ -s\theta_1 & c\theta_1 & 0 & 0 \\ 0 & 0 & 1 & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix} $$

Inverse Kinematics - PUMA 560 - Algebraic Solution

$$\left[{}^{0}_{1}T\right]^{-1} \qquad {}^{0}_{6}T$$

$$\begin{bmatrix} c_1 & s_1 & 0 & 0 \\ -s_1 & c_1 & 0 & 0 \\ 0 & 0 & 1 & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix} \begin{bmatrix} r_{11} & r_{12} & r_{13} & p_x \\ r_{21} & r_{22} & r_{23} & p_y \\ r_{31} & r_{32} & r_{33} & p_z \\ 0 & 0 & 0 & 1 \end{bmatrix} = {}^{1}_{6}T$$

$${}^{1}_{0}T \qquad {}^{0}_{6}T \qquad = {}^{1}_{6}T$$

Inverse Kinematics - PUMA 560 - Algebraic Solution

$$ {}^1_2T = \begin{bmatrix} c\theta_2 & -s\theta_2 & 0 & 0 \\ 0 & 0 & 1 & 0 \\ -s\theta_2 & -c\theta_2 & 0 & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix} $$

$$ {}^2_3T = \begin{bmatrix} c\theta_3 & -s\theta_3 & 0 & a_2 \\ s\theta_3 & c\theta_3 & 0 & 0 \\ 0 & 0 & 1 & d_3 \\ 0 & 0 & 0 & 1 \end{bmatrix} $$

$$ {}^3_4T = \begin{bmatrix} c\theta_4 & -s\theta_4 & 0 & a_3 \\ 0 & 0 & 1 & d_4 \\ -s\theta_4 & -c\theta_4 & 0 & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix} $$

$$ {}^4_5T = \begin{bmatrix} c\theta_5 & -s\theta_5 & 0 & 0 \\ 0 & 0 & -1 & 0 \\ s\theta_5 & c\theta_5 & 0 & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix} $$

$$ {}^5_6T = \begin{bmatrix} c\theta_5 & -s\theta_5 & 0 & 0 \\ 0 & 0 & 1 & 0 \\ -s\theta_5 & -c\theta_5 & 0 & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix} $$

algebraically solve for ${}^1_6T$

$$ \approx \quad {}^1_6T = \begin{bmatrix} {}^1r_{11} & {}^1r_{12} & {}^1r_{13} & {}^1p_x \\ {}^1r_{21} & {}^1r_{22} & {}^1r_{23} & {}^1p_y \\ {}^1r_{31} & {}^1r_{32} & {}^1r_{33} & {}^1p_z \\ 0 & 0 & 0 & 1 \end{bmatrix} $$

↓ elemental expressions

$$ {}^1r_{11} = c_{23}\left[c_4c_5c_6 - s_4s_6\right] - s_{23}s_5s_6, $$
$$ {}^1r_{21} = -s_4c_5c_6 - c_4s_6, $$
$$ {}^1r_{31} = -s_{23}\left[c_4c_5c_6 - s_4s_6\right] - c_{23}s_5c_6, $$

$$ {}^1r_{12} = -c_{23}\left[c_4c_5s_6 + s_4c_6\right] + s_{23}s_5s_6, $$
$$ {}^1r_{22} = s_4c_5s_6 - c_4c_6, $$
$$ {}^1r_{32} = s_{23}\left[c_4c_5s_6 + s_4c_6\right] + c_{23}s_5s_6, $$

$$ {}^1r_{13} = -c_{23}c_4s_5 - s_{23}c_5, $$
$$ {}^1r_{23} = s_4s_5, $$
$$ {}^1r_{33} = s_{23}c_4s_5 - c_{23}c_5, $$

$$ {}^1p_x = a_2c_2 + a_3c_{23} - d_4s_{23}, $$
$$ {}^1p_y = d_3, $$
$$ {}^1p_z = -a_3s_{23} - a_2s_2 - d_4c_{23}. $$

Inverse Kinematics - PUMA 560 - Algebraic Solution

$$\underbrace{\begin{bmatrix} c_1 & s_1 & 0 & 0 \\ -s_1 & c_1 & 0 & 0 \\ 0 & 0 & 1 & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix}}_{{}^1_0T} \underbrace{\begin{bmatrix} r_{11} & r_{12} & r_{13} & p_x \\ r_{21} & r_{22} & r_{23} & p_y \\ r_{31} & r_{32} & r_{33} & p_z \\ 0 & 0 & 0 & 1 \end{bmatrix}}_{{}^0_6T} = {}^1_6T$$

multiply our T's

- Equating the (2,4) elements from both sides of the equation we have

$$\underbrace{-s_1 p_x + c_1 p_y} = d_3 \qquad \theta_1$$

- To solve the equation of this form we make the trigonometric substitution

$$p_x = \rho \cos\phi$$
$$p_y = \rho \sin\phi$$

Inverse Kinematics - PUMA 560 - Algebraic Solution

$$\begin{cases} \rho = \sqrt{p_x^2 + p_y^2} \\ \phi = A\tan 2(p_x + p_y) \end{cases}$$

,

- Substituting p_x, p_y with ρ, ϕ we obtain

$$\left[c_1 s_\phi - s_1 c_\phi \right] = \frac{d_3}{\rho}$$

- Using the difference of angles formula

$$\sin(\phi - \theta_1) = \frac{d_3}{\rho}$$

Inverse Kinematics - PUMA 560 - Algebraic Solution

- Based on $$\sin^2(\phi-\theta_1)+\cos^2(\phi-\theta_1)=1$$

$$\cos(\phi-\theta_1)=\pm\sqrt{1-\frac{d_3^2}{\rho^2}}$$

- and so

$$\phi-\theta_1=A\tan 2\left(\frac{d_3}{\rho},\pm\sqrt{1-\frac{d_3^2}{\rho^2}}\right)$$

- The solution for θ_1 may be written

$$\theta_1=A\tan 2(p_y,p_x)-A\tan 2\left(\frac{d_3}{\rho},\pm\sqrt{1-\frac{d_3^2}{\rho^2}}\right)$$

- Note: we have found two possible solutions for θ_1 corresponding to the +/- sign

Inverse Kinematics - PUMA 560 - Algebraic Solution

- Equating the (1,4) element and (3,4) element

$$\begin{bmatrix} c_1 & s_1 & 0 & 0 \\ -s_1 & c_1 & 0 & 0 \\ 0 & 0 & 1 & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix} \begin{bmatrix} r_{11} & r_{12} & r_{13} & p_x \\ r_{21} & r_{22} & r_{23} & p_y \\ r_{31} & r_{32} & r_{33} & p_z \\ 0 & 0 & 0 & 1 \end{bmatrix} = {}^1_6T$$

- We obtain

$$c_1 p_x + s_1 p_y = a_3 c_{23} - d_4 s_{23} + a_2 c_2 \qquad \theta_2, \theta_3$$

$$-p_z = a_3 c_{23} + d_4 s_{23} + a_2 c_2 \qquad \theta_2, \theta_3$$

Inverse Kinematics - PUMA 560 - Algebraic Solution

- If we square the following equations and add the resulting equations

$$-s_1 p_x + c_1 p_y = d_3$$ original $(\to \theta_1)$

$$\left.\begin{aligned} c_1 p_x + s_1 p_y &= a_3 c_{23} - d_4 s_{23} + a_2 c_2 \\ -p_z &= a_3 c_{23} + d_4 s_{23} + a_2 c_2 \end{aligned}\right\}$$

Inverse Kinematics - PUMA 560 - Algebraic Solution

- we obtain

$$a_3 c_3 - d_4 s_3 = K$$

- where

$$K = \frac{p_x^2 + p_y^2 + p_z^2 - a_2^2 - a_3^2 - d_3^2 - a_4^2}{2a_2}$$

knowns

- Note that the dependence on θ_1 has be removed. Moreover the eq. for θ_3 is of the same form as the eq. for θ_1 and so may be solved by the same kind of trigonometric substitution to yield a solution for θ_3

$$\theta_3 = A\tan 2(a_3, d_4) - A\tan 2\left(K, \pm\sqrt{a_3^2 + d_4^2 - K^2}\right)$$

- Note that the +/- sign leads to two different solution for θ_3

Inverse Kinematics - PUMA 560 - Algebraic Solution

${}^0_6T = {}^0_1T\,{}^1_2T\,{}^2_3T \ldots$

goal For. Kin.

$$[{}^0_3T(\theta_1\theta_2\theta_3)]^{-1}\ {}^0_6T = \boxed{[{}^0_1T(\theta_1)]^{-1}\ {}^0_1T(\theta_1)\ {}^1_2T(\theta_2)\ {}^2_3T(\theta_3)}\ {}^3_4T(\theta_4)\ {}^4_5T(\theta_5)\ {}^5_6T(\theta_6)$$

$$\begin{bmatrix} c_1c_{23} & s_1c_{23} & -s_{23} & -a_2c_3 \\ -c_1s_{23} & -s_1s_{23} & -c_{23} & a_2s_3 \\ -s_1 & c_1 & 0 & -d_3 \\ 0 & 0 & 0 & 1 \end{bmatrix} \begin{bmatrix} r_{11} & r_{12} & r_{13} & p_x \\ r_{21} & r_{22} & r_{23} & p_y \\ r_{31} & r_{32} & r_{33} & p_z \\ 0 & 0 & 0 & 1 \end{bmatrix} = \begin{bmatrix} c_4c_5c_6 - s_4s_6 & -c_4c_5s_6 - s_4c_6 & -c_4s_5 & a_3 \\ s_5c_6 & -s_5s_6 & -c_5 & d_4 \\ -s_4c_5c_6 - c_4s_6 & s_4c_5s_6 - c_4c_6 & s_4s_5 & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix}$$

- Equating the (1,4) element and (2,4) element we obtain

$$c_1c_{23}p_x + s_1c_{23}p_y - s_{23}p_z - a_2c_3 = a_3$$

$$-c_1s_{23}p_x - s_1s_{23}p_y - c_{23}p_z + a_2s_3 = d_4$$

- These equations may be solved simultaneously for s_{23} and c_{23} resulting in

Inverse Kinematics - PUMA 560 - Algebraic Solution

$$s(\theta_2+\theta_3) \quad s_{23} = \frac{(-a_3 - a_2 c_2) p_z + (c_1 p_x + s_1 p_y)(a_2 s_3 - d_4)}{p_z^2 + (c_1 p_x + s_1 p_y)^2}$$

$$c(\theta_2+\theta_3) = c_{23} = \frac{(a_2 s_3 - d_4) p_z - (-a_3 - a_2 c_3)(c_1 p_x + s_1 p_y)}{p_z^2 + (c_1 p_x + s_1 p_y)^2}$$

- Since the denominator are equal and positive, we solve for the sum of θ_2 and θ_3 as

$$\theta_{23} = \underline{A\tan 2}[(-a_3 - a_2 c_2) p_z + (c_1 p_x + s_1 p_y)(a_2 s_3 - d_4), \\ (a_2 s_3 - d_4) p_z - (-a_3 - a_2 c_3)(c_1 p_x + s_1 p_y)]$$

- The equation computes four values of θ_{23} according to the four possible combination of solutions for θ_1 and θ_3

Inverse Kinematics - PUMA 560 - Algebraic Solution

- Then, four possible solutions for θ_2 are computed as

$$\theta_2 = \theta_{23} - \theta_3 = (\theta_2 + \theta_3) - \theta_3$$

- Equating the (1,3) and the (3,3) elements

$$\begin{bmatrix} c_1c_{23} & s_1c_{23} & -s_{23} & -a_2c_3 \\ -c_1s_{23} & -s_1s_{23} & -c_{23} & a_2s_3 \\ -s_1 & c_1 & 0 & -d_3 \\ 0 & 0 & 0 & 1 \end{bmatrix} \begin{bmatrix} r_{11} & r_{12} & r_{13} & p_x \\ r_{21} & r_{22} & r_{23} & p_y \\ r_{31} & r_{32} & r_{33} & p_z \\ 0 & 0 & 0 & 1 \end{bmatrix} = \begin{bmatrix} c_4c_5c_6 - s_4s_6 & -c_4c_5s_6 - s_4c_6 & -c_4s_5 & a_3 \\ s_5c_6 & -s_5s_6 & -c_5 & d_4 \\ -s_4c_5c_6 - c_4s_6 & s_4c_5s_6 - c_4c_6 & s_4s_5 & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix}$$

- we get

$$r_{13}c_1c_{23} + r_{23}s_1c_{23} - s_{23}r_{33} = -c_4s_5$$

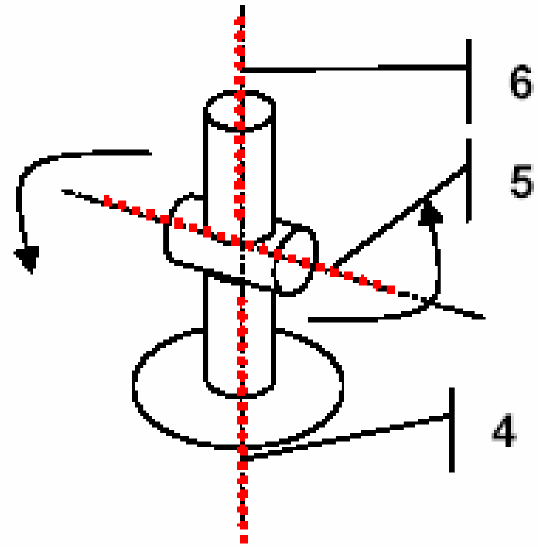
$$-r_{13}s_1 + r_{23}c_1 = s_4s_5$$

Inverse Kinematics - PUMA 560 - Algebraic Solution

- As long as $\boxed{s_5 \neq 0}$ we can solve for θ_4

$$\theta_4 = A\tan 2(-r_{13}s_1 + r_{23}c_1, -r_{13}c_1c_{23} - r_{23}s_1c_{23} + s_{23}r_{33})$$

- When $\theta_5 = 0$ the manipulator is in a ***singular configuration*** in which joint axes 4 and 6 line up and cause the same motion of the last link of the robot. In this case all that can be solved for is the sum or difference of θ_4 and θ_6. This situation is detected by checking whether both arguments of Atan2 are near zero. If so θ_4 is chosen arbitrary (usually chosen to be equal to the present value of joint 4), and θ_6 is computed later, it will be computed accordingly



Inverse Kinematics - PUMA 560 - Algebraic Solution

$$[{}^0_4T(\theta_1,\theta_2,\theta_3,\theta_4)]^{-1}\ {}^0_6T = [{}^0_4T(\theta_1,\theta_2,\theta_3,\theta_4)]^{-1}\ {}^0_1T(\theta_1)\ {}^1_2T(\theta_2)\ {}^2_3T(\theta_3)\ {}^3_4T(\theta_4)\ {}^4_5T(\theta_5)\ {}^5_6T(\theta_6)$$

$$\begin{bmatrix} c_1c_{23}c_4+s_1s_4 & s_1c_{23}c_4-c_1s_4 & -s_{23}c_4 & -a_2c_3c_4+d_3s_4-a_3c_4 \\ -c_1c_{23}s_4+s_1c_4 & -s_1c_{23}s_4-c_1c_4 & s_{23}s_4 & a_2c_3s_4+d_3c_4-a_3s_4 \\ -c_1s_{23} & -s_1s_{23} & c_{23} & a_2s_3-d_4 \\ 0 & 0 & 0 & 1 \end{bmatrix} \begin{bmatrix} r_{11} & r_{12} & r_{13} & p_x \\ r_{21} & r_{22} & r_{23} & p_y \\ r_{31} & r_{32} & r_{33} & p_z \\ 0 & 0 & 0 & 1 \end{bmatrix} = \begin{bmatrix} c_5c_6 & -c_5s_6 & -s_5 & 0 \\ s_6 & c_6 & 0 & 0 \\ s_5c_6 & -s_5s_6 & c_5 & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix}$$

- Equating the (1,3) and the (3,3) elements we get

$$r_{13}(c_1c_{23}c_4+s_1s_4)+r_{23}(s_1c_{23}c_4-c_1s_4)-r_{33}(s_{23}c_4)=s_5$$

$$r_{13}(-c_1s_{23})+r_{23}(-s_1s_{23})+r_{33}(-c_{23})=c_5$$

Inverse Kinematics - PUMA 560 - Algebraic Solution

- We can solve for θ_5

$$\theta_5 = A\tan 2(s_5, c_5)$$

$$[{}^0_5T(\theta_1,\theta_2,\theta_3,\theta_4,\theta_5)]^{-1}\ {}^0_6T = \boxed{[{}^0_5T(\theta_1,\theta_2,\theta_3,\theta_4,\theta_5)]^{-1}\ {}^0_1T(\theta_1)\ {}^1_2T(\theta_2)\ {}^2_3T(\theta_3)\ {}^3_4T(\theta_4)\ {}^4_5T(\theta_5)}\ {}^5_6T(\theta_6)$$

$$r_{11}(c_1c_{23}s_4 + s_1c_4) - r_{21}(s_1c_{23}s_4 + c_1c_4) + r_{31}(s_{23}s_4) = s_6$$

$$r_{11}[(c_1c_{23}c_4 + s_1s_4)c_5 - c_1s_{23}s_5] + r_{21}[(s_1c_{23}c_4 - c_1s_4)c_5 - s_1s_{23}s_5] - r_{31}(s_{23}c_4c_5 + c_{23}s_5) = c_6$$

$$\theta_6 = A\tan 2(s_6, c_6)$$

Inverse Kinematics - PUMA 560 - Algebraic Solution

- Summary - Number of Solutions

- Four solution

$$\theta_1 = A\tan 2(p_y, p_x) - A\tan 2\left(\frac{d_3}{\rho}, \pm\sqrt{1-\frac{d_3^2}{\rho^2}}\right)$$

$$\theta_3 = A\tan 2(a_3, d_4) - A\tan 2\left(K, \pm\sqrt{a_3^2 + d_4^2 - K^2}\right)$$

- For each of the four solutions the wrist can be flipped

$$\theta_4' = \theta_4 + 180^o$$

$$\theta_5' = -\theta_5$$

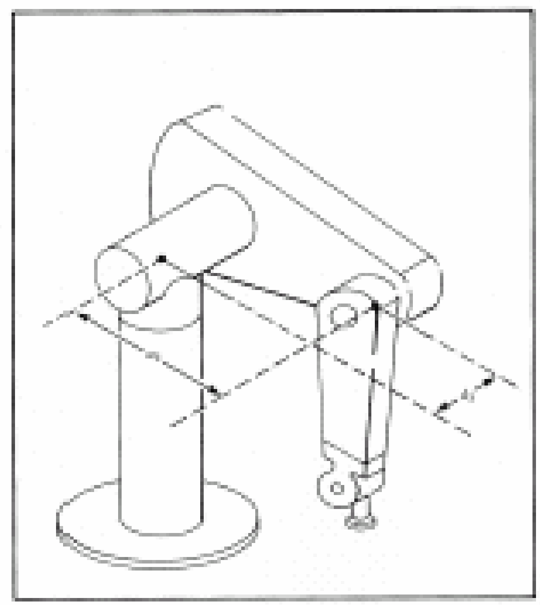
$$\theta_6' = \theta_6 + 180^o$$

Inverse Kinematics - PUMA 560 - Algebraic Solution

- After all eight solutions have been computed, some or all of them may have to be discarded because of joint limit violations.
- Of the remaining valid solutions, usually the one closest to the present manipulator configuration is chosen.

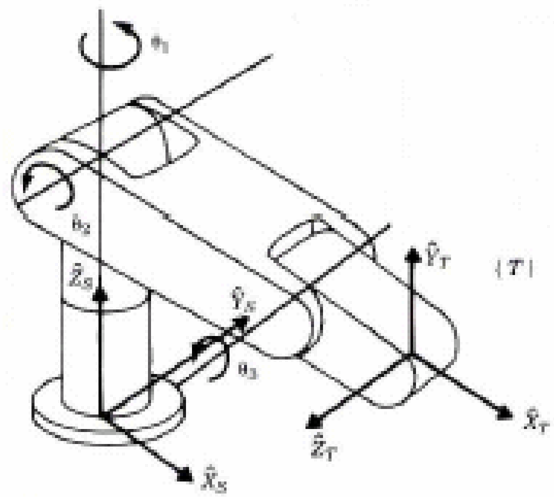
Central Topic - Inverse Manipulator Kinematics -Examples

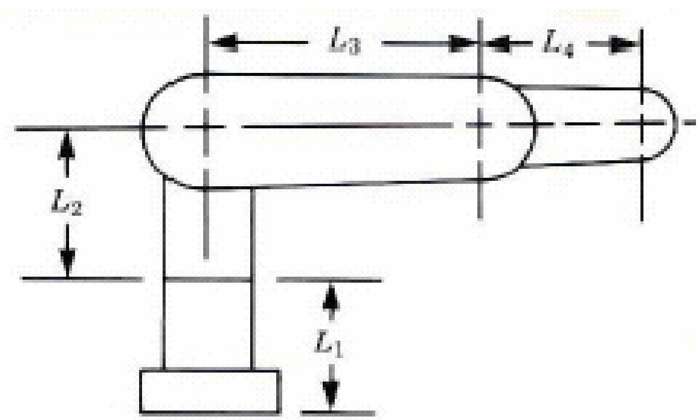
- **Geometric Solution - Concept**
  - Decompose spatial geometry into several plane geometry
  - **Example** - 3D - RRR (3R) manipulators - Geometric Solution
- **Algebraic Solution** (closed form) –
  - Piepers Method - Last three consecutive axes intersect at one point
  - **Example** - Puma 560



Algebraic Solution by Reduction to Polynomial - Example

- ***Given:***
  - ***Manipulator Geometry***
  - ***Goal Point Definition***: The position x_d, y_d, z_d of the wrist in space

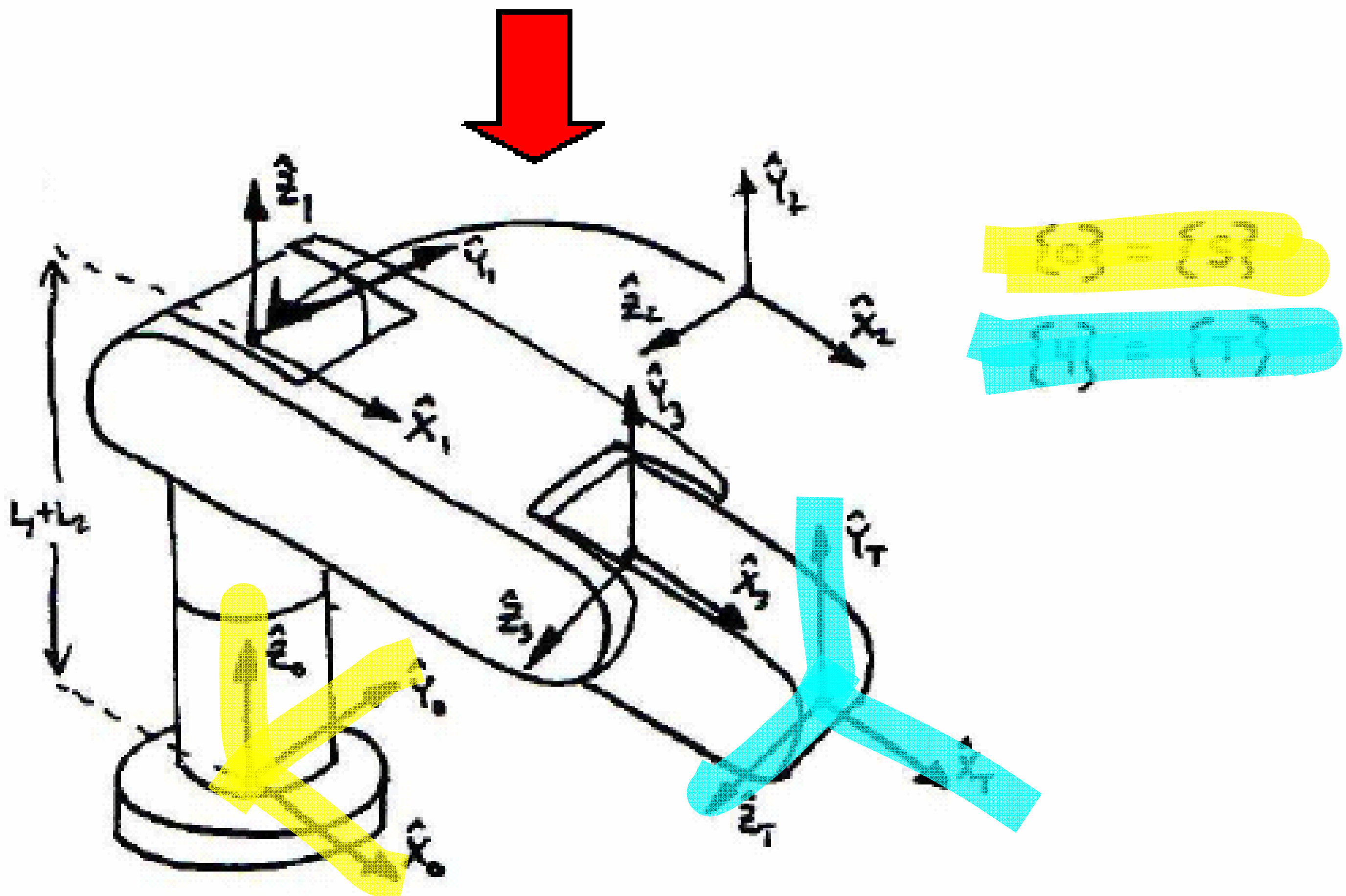




- ***Problem:***

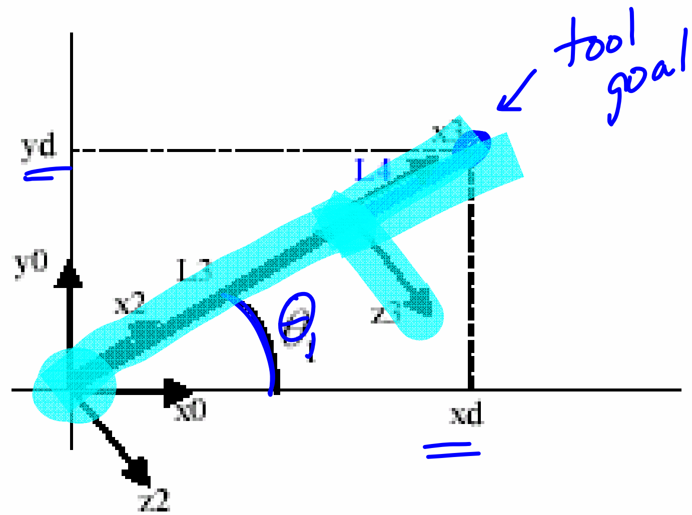
What are the joint angles ($\theta_1, \theta_2, \theta_3$) as a function of the goal (wrist position and orientation)

Algebraic Solution by Reduction to Polynomial - Example



Algebraic Solution by Reduction to Polynomial - Example

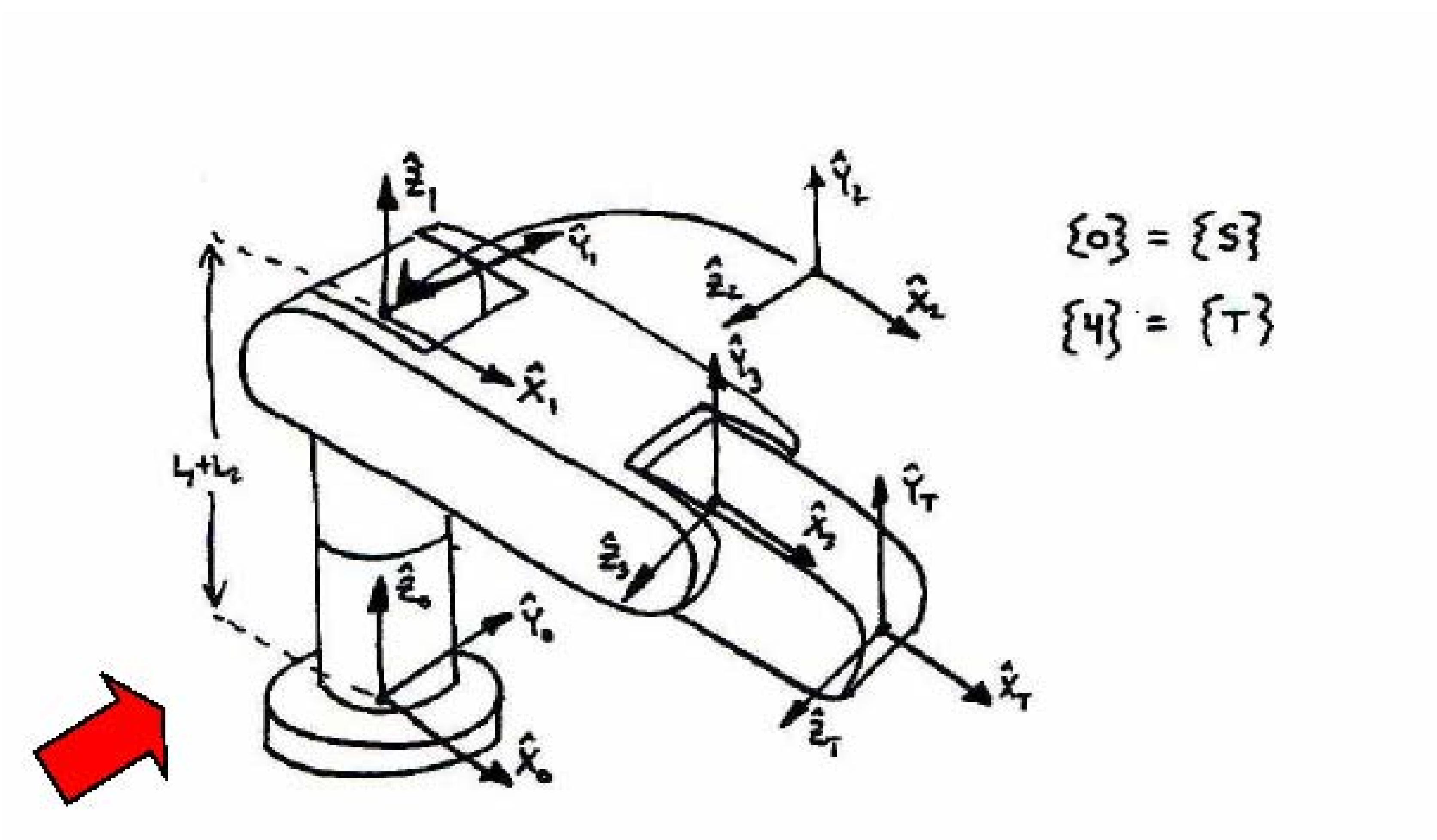
- The planar geometry - top view of the robot



$$\boxed{\theta_1 = A\tan 2(y_d, x_d)}$$

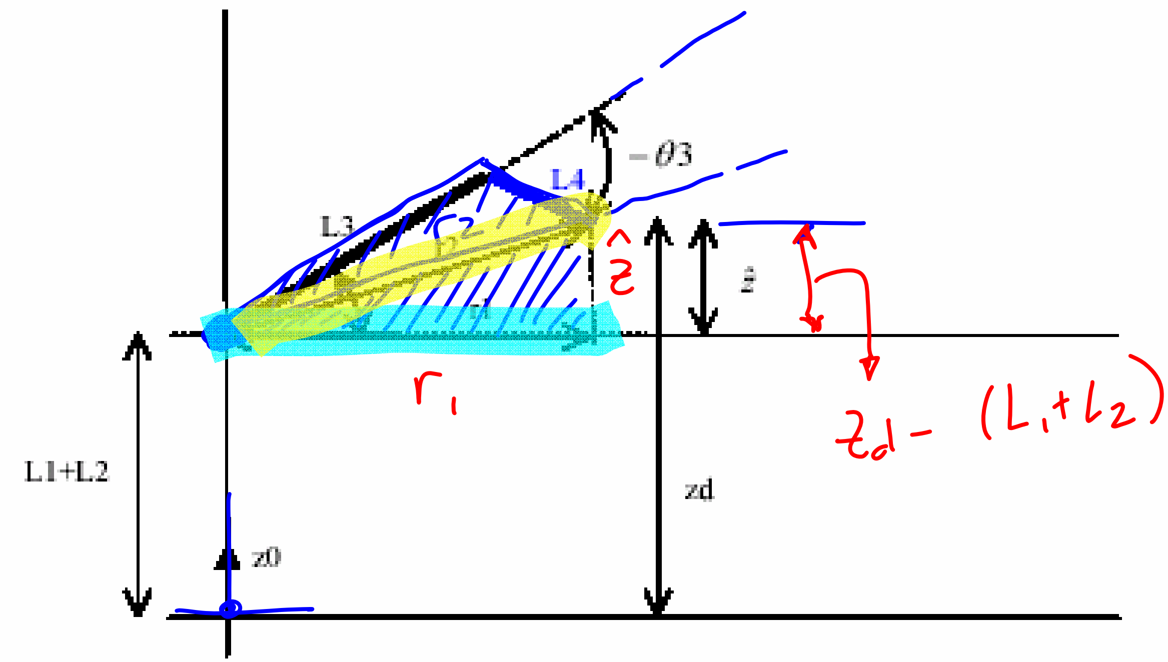
$$r_1 = \sqrt{x_d^2 + y_d^2}$$

Algebraic Solution by Reduction to Polynomial - Example



Algebraic Solution by Reduction to Polynomial - Example

- The planar geometry - side view of the robot:



$$r_2 = \sqrt{r_1^2 + \hat{z}^2} = \sqrt{x_d^2 + y_d^2 + \hat{z}^2} = \sqrt{x_d^2 + y_d^2 + \left(z_d - (L_1 + L_2)\right)^2}$$

- where

$$\hat{z} = z_d - (L_1 + L_2)$$

Algebraic Solution by Reduction to Polynomial - Example

- By applying the law of cosines, we get

$$r_2^2 = L_3^2 + L_4^2 - 2L_3L_4\cos(180+\theta_3) = L_3^2 + L_4^2 + 2L_3L_4\cos(\theta_3)$$

- Rearranging gives

$$c_3 = \frac{r_2^2 - (L_3^2 + L_4^2)}{2L_3L_4} \qquad s^2 + c^2 = 1$$

- and

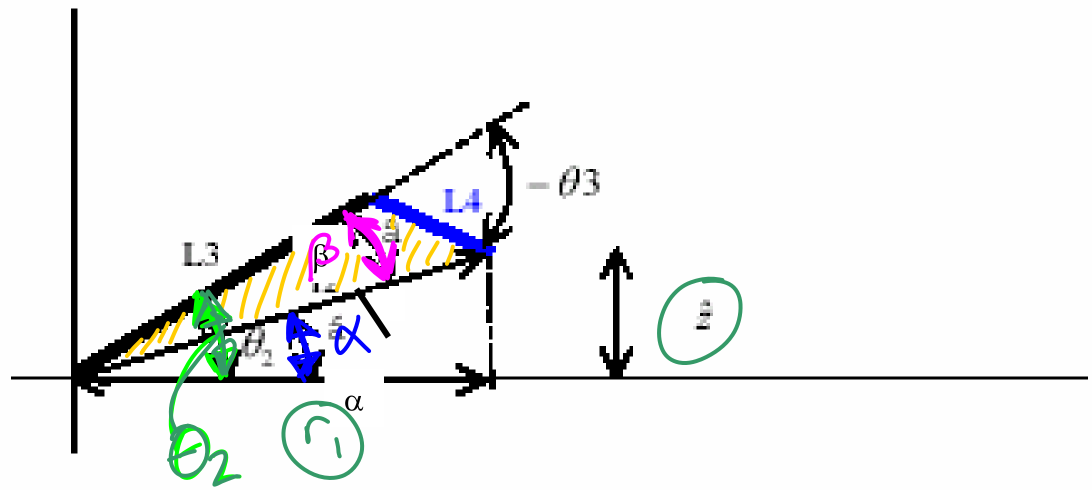
$$s_3 = \sqrt{1 - c_3^2}$$

- Solving for θ_3 we get

$$\boxed{\theta_3 = Atan2(\pm\sqrt{1-c_3^2}, c_3)}$$

- Where c_3 is defined above in terms of known parameters L_3, L_4, x_d, y_d, and z_d

Algebraic Solution by Reduction to Polynomial - Example



- Finally we need to solve for θ_2

$$\theta_2 = \alpha + \beta$$

$$\alpha = A\tan 2(\hat{z}, r_1)$$

- where $r_1 = \sqrt{x_d^2 + y_d^2}$ $\quad \hat{z} = z_d - (L_1 + L_2)$

Algebraic Solution by Reduction to Polynomial - Example

- Based on the law of cosines we can solve for β

$$L_4^2 = r_2^2 + L_3^2 - 2r_2 L_3 \cos(\beta)$$

$$c_\beta = \frac{r_2^2 + L_3^2 - L_4^2}{2r_2 L_3}$$

$s^2 + c^2 = 1$

$$\beta = A\tan 2(\pm\sqrt{1 - c_\beta^2}, c_\beta)$$

$$\boxed{\theta_2 = A\tan 2(z_d - (L_1 + L_2), \sqrt{x_d^2 + y_d^2}) + A\tan 2(\pm\sqrt{1 - c_\beta^2}, c_\beta)}$$

Algebraic Solution by Reduction to Polynomial - Example

- Summary

$$\theta_1 = A\tan 2(y_d, x_d)$$

$$\theta_2 = A\tan 2(z_d - (L_1 + L_2), \sqrt{x_d^2 + y_d^2}) +$$

$$A\tan 2(\pm\sqrt{1 - \left(\frac{x_d^2 + y_d^2 + \left(z_d - (L_1 + L_2)\right)^2 + L_3^2 - L_4^2}{2\sqrt{x_d^2 + y_d^2 + (z_d - (L_1 + L_2)} L_3)^2}\right)^2}, \frac{x_d^2 + y_d^2 + \left(z_d - (L_1 + L_2)\right)^2 + L_3^2 - L_4^2}{2\sqrt{x_d^2 + y_d^2 + (z_d - (L_1 + L_2)} L_3)^2})$$

$$\theta_3 = A\tan(\pm\sqrt{1 - \left[\frac{x_d^2 + y_d^2 + \left(z_d - (L_1 + L_2)\right)^2 - (L_3^2 + L_4^2)}{2L_3 L_4}\right]^2}, \frac{x_d^2 + y_d^2 + \left(z_d - (L_1 + L_2)\right)^2 - (L_3^2 + L_4^2)}{2L_3 L_4})$$

Algebraic Solution by Reduction to Polynomial

- Transcendental equations are difficult to solve because they are a function of $c\theta$, $s\theta$

$$f(c\theta, s\theta) = k$$

- Making the following substitutions yields an expression in terms of a single variable u
- Using this substitution, transcendental equations are converted into polynomial equations

$$u = \tan\frac{\theta}{2}$$

$$\cos\theta = \frac{1-u^2}{1+u^2}$$

$$\sin\theta = \frac{2u}{1+u^2}$$

Algebraic Solution by Reduction to Polynomial - Example

- Transcendental equation

$$\underbrace{ac\theta + bs\theta = c}$$

- Substitute $c\theta, s\theta$ with the following equations

$$\cos\theta = \frac{1-u^2}{1+u^2}$$

$$\sin\theta = \frac{2u}{1+u^2}$$

- yields

$$a(1-u^2) + 2bu = c(1+u^2)$$

$$(a+c)u^2 - 2bu + (c-a) = 0$$

Algebraic Solution by Reduction to Polynomial - Example

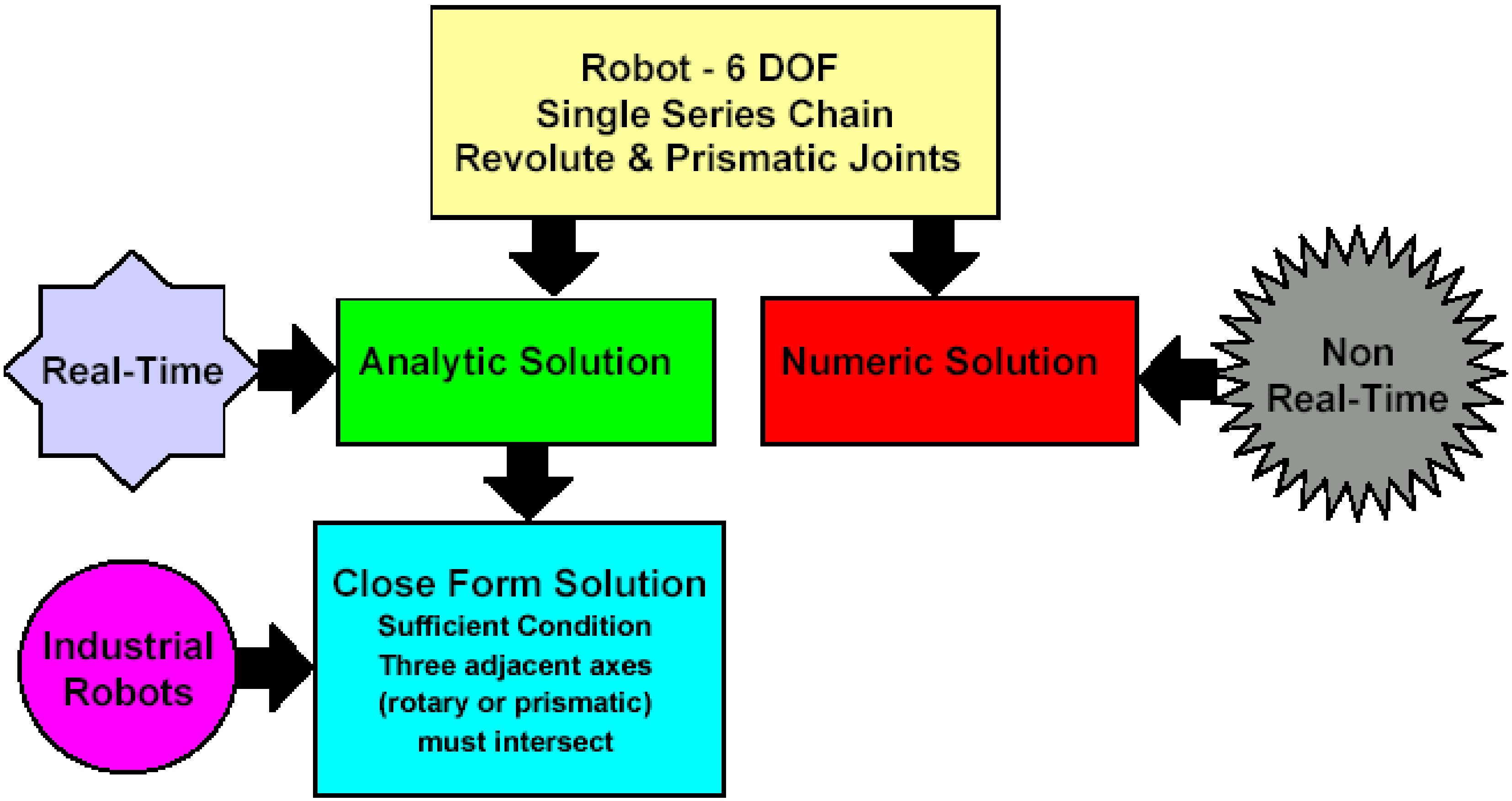
- Which is solved by the quadratic formula to be

$$u = \frac{b \pm \sqrt{b^2 + a^2 - c^2}}{a+c}$$

$$\theta = 2\tan^{-1}\left(\frac{b \pm \sqrt{b^2 + a^2 - c^2}}{a+c}\right)$$

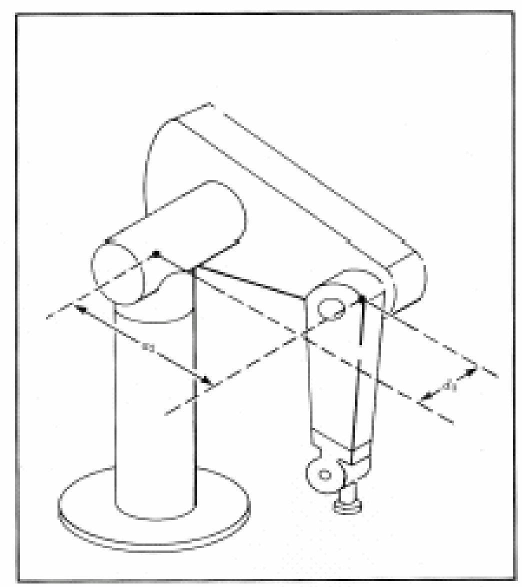
- Note
  - If u is complex there is no real solution to the original transcendental equation
  - If $a+c=0$ then $\theta = 180^o$

Solvability



Pieper's Solution - Three consecutive Axes Intersect

- **Pieper's Solution**
  - Closed form solution for a serial 6 DOF in which **three consecutive axes intersect at a point** (including robots with three consecutive parallel axes, since they meet at a point at infinity)
- Pieper's method applies to the majority of commercially available industrial robots
  - Example: (Puma 560)
    - All 6 joints are revolute joints
    - The last 3 joints are intersecting



Pieper's Solution - Three consecutive Axes Intersect

- ***Given:***
  - ***Manipulator Geometry:*** 6 DOF & DH parameters
    - All 6 joints are revolute joints
    - The last 3 joints are intersecting
  - ***Goal Point Definition*:** The position and orientation of the wrist in space

forward kin.

$$ {}^{0}_{6}T = {}^{0}_{1}T\,{}^{1}_{2}T\,{}^{2}_{3}T\,{}^{3}_{4}T\,{}^{4}_{5}T\,{}^{5}_{6}T = \begin{bmatrix} r_{11} & r_{12} & r_{13} & p_x \\ r_{21} & r_{22} & r_{23} & p_y \\ r_{31} & r_{32} & r_{33} & p_z \\ 0 & 0 & 0 & 1 \end{bmatrix} $$

- ***Problem:***
  - What are the joint angles ($\theta_1, \theta_2, \theta_3, \theta_4, \theta_5, \theta_6$) as a function of the goal (wrist position and orientation)

Pieper's Solution - Three consecutive Axes Intersect

- When the last three axes of a 6 DOF robot intersect, the origins of link frame {4}, {5}, and {6} are all located at the point of intersection. This point is given in the base coordinate system as

$$\underbrace{{}^{0}P_{4org}} = {}^{0}_{1}T\,\underbrace{{}^{1}_{2}T\,{}^{2}_{3}T\,{}^{3}P_{4org}}$$

- From the general forward kinematics method for determining homogeneous transforms using DH parameters, we know:

$^{3}P_{4org}$

$$
{}^{3}_{4}T = \quad {}^{i-1}_{i}T = \begin{array}{c}
\begin{array}{cc} \qquad\qquad {}^{i-1}_{i}R \qquad\qquad\qquad & {}^{i-1}P_{iorg} \end{array} \\
\left[\begin{array}{ccc|c}
c\theta_i & -s\theta_i & 0 & a_{i-1} \\
s\theta_i c\alpha_{i-1} & c\theta_i c\alpha_{i-1} & -s\alpha_{i-1} & -s\alpha_{i-1}d_i \\
s\theta_i s\alpha_{i-1} & c\theta_i s\alpha_{i-1} & c\alpha_{i-1} & c\alpha_{i-1}d_i \\
0 & 0 & 0 & 1
\end{array}\right]
\end{array}
$$

Pieper's Solution - Three consecutive Axes Intersect

- For i=4

$$
{}^3_4T = \begin{array}{c}
\begin{array}{cc} \qquad\qquad\qquad {}^3_4R \qquad\qquad\qquad & \quad {}^3P_{4org} \end{array} \\
\begin{bmatrix}
c\theta_4 & -s\theta_4 & 0 & a_3 \\
s\theta_4 c\alpha_3 & c\theta_4 c\alpha_3 & -s\alpha_3 & -s\alpha_3 d_4 \\
s\theta_4 s\alpha_3 & c\theta_4 s\alpha_3 & c\alpha_3 & c\alpha_3 d_4 \\
0 & 0 & 0 & 1
\end{bmatrix}
\end{array}
$$

- Using the fourth column and substituting for ${}^3P_{4org}$ we find

$$
{}^0P_{4org} = {}^0_1T\,{}^1_2T\,{}^2_3T\,{}^3P_{4org} = {}^0_1T\,{}^1_2T\,{}^2_3T \overset{\text{4th column}}{\begin{bmatrix} a_3 \\ -s\alpha_3 d_4 \\ c\alpha_3 d_4 \\ 1 \end{bmatrix}}
\qquad
{}^0P_{4org} = {}^0_1T\,{}^1_2T\,{}^2_3T\,{}^3P_{4org} = {}^0_1T\,{}^1_2T \begin{bmatrix} f_1(\theta_3) \\ f_2(\theta_3) \\ f_3(\theta_3) \\ 1 \end{bmatrix}
$$

Pieper's Solution - Three consecutive Axes Intersect

- where $$\begin{bmatrix} f_1(\theta_3) \\ f_2(\theta_3) \\ f_3(\theta_3) \\ 1 \end{bmatrix} = {}^2_3T \begin{bmatrix} a_3 \\ -s\alpha_3 d_4 \\ c\alpha_3 d_4 \\ 1 \end{bmatrix}$$

${}^3P_{4org}$

expand T

$$\begin{bmatrix} f_1(\theta_3) \\ f_2(\theta_3) \\ f_3(\theta_3) \\ 1 \end{bmatrix} = \begin{bmatrix} c\theta_3 & -s\theta_3 & 0 & a_2 \\ s\theta_3 c\alpha_2 & c\theta_3 c\alpha_2 & -s\alpha_2 & -s\alpha_2 d_3 \\ s\theta_3 s\alpha_2 & c\theta_3 s\alpha_2 & c\alpha_2 & c\alpha_2 d_3 \\ 0 & 0 & 0 & 1 \end{bmatrix} \begin{bmatrix} a_3 \\ -s\alpha_3 d_4 \\ c\alpha_3 d_4 \\ 1 \end{bmatrix}$$

multiply →

$$f_1(\theta_3) = a_3 c_3 + d_4 s\alpha_3 s_3 + a_2$$
$$f_2(\theta_3) = a_3 c\alpha_2 s_3 - d_4 s\alpha_3 c\alpha_2 c_3 - d_4 s\alpha_2 c\alpha_3 - d_3 s\alpha_2$$
$$f_3(\theta_3) = a_3 s\alpha_2 s_3 - d_4 s\alpha_3 s\alpha_2 c_3 + d_4 c\alpha_2 c\alpha_3 + d_3 c\alpha_2$$

Pieper's Solution - Three consecutive Axes Intersect

- Repeating the same process again

$$
{}^0P_{4org} = {}^0_1T\,{}^1_2T\,{}^2_3T\,{}^3P_{4org} = {}^0_1T\,{}^1_2T \begin{bmatrix} f_1(\theta_3) \\ f_2(\theta_3) \\ f_3(\theta_3) \\ 1 \end{bmatrix}
$$

from last slide

g's

$$
\begin{bmatrix} g_1(\theta_2) \\ g_2(\theta_2) \\ g_3(\theta_2) \\ 1 \end{bmatrix} = {}^1_2T \begin{bmatrix} f_1(\theta_3) \\ f_2(\theta_3) \\ f_3(\theta_3) \\ 1 \end{bmatrix}
$$

${}^1_2T$

${}^2_3T\,{}^3P_{4org}$

$$
\begin{bmatrix} g_1(\theta_2) \\ g_2(\theta_2) \\ g_3(\theta_2) \\ 1 \end{bmatrix} = \begin{bmatrix} c\theta_2 & -s\theta_2 & 0 & a_1 \\ s\theta_2 c\alpha_1 & c\theta_2 c\alpha_2 & -s\alpha_1 & -s\alpha_1 d_2 \\ s\theta_2 s\alpha_1 & c\theta_2 s\alpha_1 & c\alpha_1 & c\alpha_1 d_2 \\ 0 & 0 & 0 & 1 \end{bmatrix} \begin{bmatrix} f_1(\theta_3) \\ f_2(\theta_3) \\ f_3(\theta_3) \\ 1 \end{bmatrix}
$$

Pieper's Solution - Three consecutive Axes Intersect

$$g_1(\theta_2) = c_2 f_1 + s_2 f_2 + a_1$$
$$g_2(\theta_2) = s_3 s\alpha_1 s_3 f_1 + c_2 c\alpha_1 f_2 - s\alpha_1 f_3 - d_2 s\alpha_1$$
$$g_3(\theta_2) = s_2 s\alpha_1 s_2 f + c_2 s\alpha_1 f_2 + c\alpha_1 f_3 + d_2 c\alpha_1$$

- Repeating the same process for the last time

$$^0P_{4org} = {}^0_1T\,{}^1_2T\,{}^2_3T\,{}^3P_{4org} = {}^0_1T \begin{bmatrix} g_1(\theta_2) \\ g_2(\theta_2) \\ g_2(\theta_2) \\ 1 \end{bmatrix}$$

^0_1T $\qquad$ $^1_2T\,{}^2_3T\,{}^3P_{4org}$

$$^0P_{4org} = \begin{bmatrix} c\theta_1 & -s\theta_1 & 0 & a_0 \\ s\theta_1 c\alpha_0 & c\theta_1 c\alpha_0 & -s\alpha_0 & -s\alpha_0 d_1 \\ s\theta_1 s\alpha_0 & c\theta_1 s\alpha_0 & c\alpha_0 & c\alpha_0 d_1 \\ 0 & 0 & 0 & 1 \end{bmatrix} \begin{bmatrix} g_1(\theta_2) \\ g_2(\theta_2) \\ g_3(\theta_2) \\ 1 \end{bmatrix}$$

Pieper's Solution - Three consecutive Axes Intersect

- ***Frame {0}*** - The frame attached to the base of the robot or link 0 called frame {0} This frame does not move and for the problem of arm kinematics can be considered as the ***reference frame.***

- Assign {0} to match {1} when the first joint **variable is zero**

$$\theta_1 \neq 0 \qquad \alpha_0 = d_1 = a_0 = 0$$

$$ {}^{0}P_{4org} = \begin{bmatrix} c\theta_1 & -s\theta_1 & 0 & a_0 \\ s\theta_1 c\alpha_0 & c\theta_1 c\alpha_0 & -s\alpha_0 & -s\alpha_0 d_1 \\ s\theta_1 s\alpha_0 & c\theta_1 s\alpha_0 & c\alpha_0 & c\alpha_0 d_1 \\ 0 & 0 & 0 & 1 \end{bmatrix} \begin{bmatrix} g_1(\theta_2) \\ g_2(\theta_2) \\ g_3(\theta_2) \\ 1 \end{bmatrix} $$

$$ {}^{0}P_{4org} = \begin{bmatrix} c_1 g_1 - s_1 g_2 \\ s_1 g_1 + c_1 g_2 \\ g_3 \\ 1 \end{bmatrix} \Rightarrow f(\theta_1) $$

Pieper's Solution - Three consecutive Axes Intersect

- Through algebraic manipulation of these equations, we can solve for the desired joint angles ($\theta_1, \theta_2, \theta_3$).
- The first step is to square the magnitude of the distance from the frame {0} origin to frame {4} origin.

$$r^2 = \left({}^0P_{4orgx}\right)^2 + \left({}^0P_{4orgy}\right)^2 + \left({}^0P_{4orgz}\right)^2 = g_1^2 + g_2^2 + g_3^2$$

- Using the previously define function for g_i we have

$$r^2 = f_1^2 + f_2^2 + f_3^2 + a_1^2 + d_2^2 + 2d_2 f_3 + a_1\left(c_2 f_1 - s_2 f_2\right)$$

Pieper's Solution - Three consecutive Axes Intersect

$$r^2 = \underbrace{\overset{k_1}{f_1^2} + \overset{k_2}{f_2^2} + f_3^2 + \cancelto{0}{a_1^2} + d_2^2 + 2d_2 f_3}_{k_3} + \cancelto{0}{a_1(c_2 f_1 - s_2 f_2)}$$

$$Z = {}^0P^2_{4orgz} = g_3$$

- Applying a substitution of temporary variables, we can write the magnitude squared term along with the z-component of the {0} frame origin to the {4} frame origin distance.

$$r^2 = (k_1 c_2 + k_2 s_2)2a_1 + k_3$$

$$Z = (k_1 s_2 - k_2 c_2)s\alpha_1 + k_4$$

$$k_1 = f_1$$

$$k_2 = -f_2$$

$$k_3 = f_1^2 + f_2^2 + f_3^2 + a_1^2 + d_2^2 + 2d_2 f_3$$

$$k_4 = f_3 c\alpha_1 + d_2 c\alpha_1$$

- These equations are useful because dependence on θ_1 has been eliminated, and dependence on θ_2 takes a simple form

Pieper's Solution - Three consecutive Axes Intersect

- Consider 3 cases while solving for θ_3 :

- **Case 1** - $a_1 = 0$

Case 2 - $s\alpha_1 = 0$

Case 3 - general

$$r^2 = k_3$$

$$k_3 = f_1^2 + f_2^2 + f_3^2 + a_1^2 + d_2^2 + 2d_2 f_3$$

$$\begin{cases} f_1(\theta_3) = a_3 c_3 + d_4 s\alpha_3 s_3 + a_2 \\ f_2(\theta_3) = a_3 c\alpha_2 s_3 - d_4 s\alpha_3 c\alpha_2 c_3 - d_4 s\alpha_2 c\alpha_3 - d_3 s\alpha_2 \\ f_3(\theta_3) = a_3 s\alpha_2 s_3 - d_4 s\alpha_3 s\alpha_2 c_3 + d_4 c\alpha_2 c\alpha_3 + d_3 c\alpha_2 \end{cases}$$

- Solution Methodology - Reduction to Ploynomial => Quadratic Equation

(θ_3)

$$u = \tan\frac{\theta}{2} \qquad \cos\theta = \frac{1-u^2}{1+u^2} \qquad \sin\theta = \frac{2u}{1+u^2}$$

Pieper's Solution - Three consecutive Axes Intersect

- **Case 2** - $s\alpha_1 = 0$

$$Z = k_4$$

$$k_4 = f_3 c\alpha_1 + d_2 c\alpha_1$$

$$f_3(\theta_3) = a_3 s\alpha_2 s_3 - d_4 s\alpha_3 s\alpha_2 c_3 + d_4 c\alpha_2 c\alpha_3 + d_3 c\alpha_2$$

- Solution Methodology - Reduction to Ploynomial => Quadratic Equation

$$u = \tan\frac{\theta}{2} \qquad \cos\theta = \frac{1-u^2}{1+u^2} \qquad \sin\theta = \frac{2u}{1+u^2}$$

Pieper's Solution - Three consecutive Axes Intersect

- **Case 3 (General case)** : We can find θ_3 through the following algebraic manipulation:

r, z

$$\frac{r^2 - k_3}{2a_1} = \left(k_1 c_2 + k_2 s_2\right)$$

$$\frac{Z - k_4}{s\alpha_1} = \left(k_1 s_2 - k_2 c_2\right)$$

- squaring both sides, we find

$$\left(\frac{r^2 - k_3}{2a_1}\right)^2 = \left(k_1 c_2 + k_2 s_2\right)^2 = k_1^2 c_2^2 + k_2^2 s_2^2 + 2k_1 k_2 c_2 s_2$$

$$\left(\frac{Z - k_4}{s\alpha_1}\right)^2 = \left(k_1 s_2 - k_2 c_2\right)^2 = k_1^2 s_2^2 + k_2^2 c_2^2 - 2k_1 k_2 c_2 s_2$$

Pieper's Solution - Three consecutive Axes Intersect

- Adding these two equations together and simplifying using the trigonometry identity (Reduction to Ploynomial), we find a fourth order equation for θ_3

$$\left(\frac{r^2-k_3}{2a_1}\right)^2+\left(\frac{Z-k_4}{s\alpha_1}\right)^2=k_1^2+k_2^2$$

$$k_1=f_1$$
$$k_2=-f_2$$
$$k_3=f_1^2+f_2^2+f_3^2+a_1^2+d_2^2+2d_2f_3$$
$$k_4=f_3c\alpha_1+d_2c\alpha_1$$

$$f_1(\theta_3)=a_3c_3+d_4s\alpha_3s_3+a_2$$
$$f_2(\theta_3)=a_3c\alpha_2s_3-d_4s\alpha_3c\alpha_2c_3-d_4s\alpha_2c\alpha_3-d_3s\alpha_2$$
$$f_3(\theta_3)=a_3s\alpha_2s_3-d_4s\alpha_3s\alpha_2c_3+d_4c\alpha_2c\alpha_3+d_3c\alpha_2$$

Pieper's Solution - Three consecutive Axes Intersect

- With θ_3 solved, substitute into r^2, Z to find θ_2

$$r^2 = (k_1 c_2 + k_2 s_2) 2a_1 + k_3$$
$$Z = (k_1 s_2 - k_2 c_2) s\alpha_1 + k_4$$

$$k_1 = f_1$$
$$k_2 = -f_2$$
$$k_3 = f_1^2 + f_2^2 + f_3^2 + a_1^2 + d_2^2 + 2d_2 f_3$$
$$k_4 = f_3 c\alpha_1 + d_2 c\alpha_1$$

$$f_1(\theta_3) = a_3 c_3 + d_4 s\alpha_3 s_3 + a_2$$
$$f_2(\theta_3) = a_3 c\alpha_2 s_3 - d_4 s\alpha_3 c\alpha_2 c_3 - d_4 s\alpha_2 c\alpha_3 - d_3 s\alpha_2$$
$$f_3(\theta_3) = a_3 s\alpha_2 s_3 - d_4 s\alpha_3 s\alpha_2 c_3 + d_4 c\alpha_2 c\alpha_3 + d_3 c\alpha_2$$

Pieper's Solution - Three consecutive Axes Intersect

- With θ_2, θ_3 solved, substitute into ${}^0P_{4org}$ to find

$$
{}^0P_{4org} = \begin{bmatrix} c_1 g_1 - s_1 g_2 \\ s_1 g_1 + c_1 g_2 \\ g_3 \\ 1 \end{bmatrix}
$$

$$
{}^0P_{4orgx} = c_1 g_1 - s_1 g_2
$$

$$
{}^0P_{4orgy} = s_1 g_1 + c_1 g_2
$$

$$
\begin{aligned}
g_1(\theta_2) &= c_2 f_1 + s_2 f_2 + a_1 \\
g_2(\theta_2) &= s_3 s\alpha_1 s_3 f_1 + c_2 c\alpha_1 f_2 - s\alpha_1 f_3 - d_2 s\alpha_1 \\
g_3(\theta_2) &= s_2 s\alpha_1 s_2 f + c_2 s\alpha_1 f_2 + c\alpha_1 f_3 + d_2 c\alpha_1
\end{aligned}
$$

$$
\begin{aligned}
f_1(\theta_3) &= a_3 c_3 + d_4 s\alpha_3 s_3 + a_2 \\
f_2(\theta_3) &= a_3 c\alpha_2 s_3 - d_4 s\alpha_3 c\alpha_2 c_3 - d_4 s\alpha_2 c\alpha_3 - d_3 s\alpha_2 \\
f_3(\theta_3) &= a_3 s\alpha_2 s_3 - d_4 s\alpha_3 s\alpha_2 c_3 + d_4 c\alpha_2 c\alpha_3 + d_3 c\alpha_2
\end{aligned}
$$

- Solve for θ_1 using the reduction to polynomial method

Pieper's Solution - Three consecutive Axes Intersect

- To complete our solution we need to solve for $\theta_4, \theta_5, \theta_6$
- Since the last three axes intersect these joint angle affect the orientation of only the last link. We can compute them based only upon the rotation portion of the specified goal ${}^0_6R$

$${}^0_6T = \begin{bmatrix} {}^0_6R & \cancel{{}^0P_{6org}} \\ 0\ 0\ 0 & 1 \end{bmatrix}$$

$${}^4_6R = {}^4_0R\,{}^0_6R$$

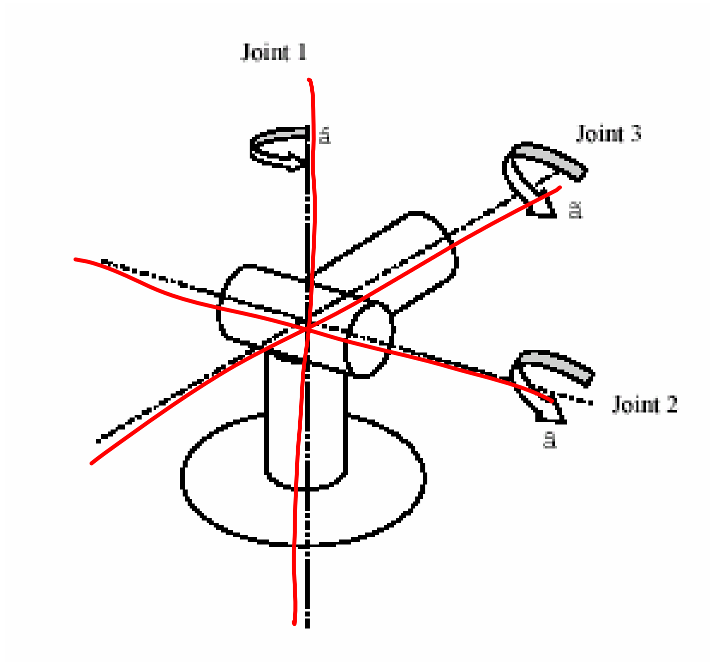
$${}^4_6R\Big|_{\theta_4=0} = {}^0_4R^{-1}\Big|_{\theta_4=0}\ {}^0_6R$$

$\theta_4 = 0$

- ${}^0_4R\Big|_{\theta_4=0}$ - The orientation of link frame {4} relative to the base frame {0} when $\theta_4 = 0$
- $\theta_4, \theta_5, \theta_6$ are the Euler angles applied to ${}^4_6R\Big|_{\theta_4=0}$

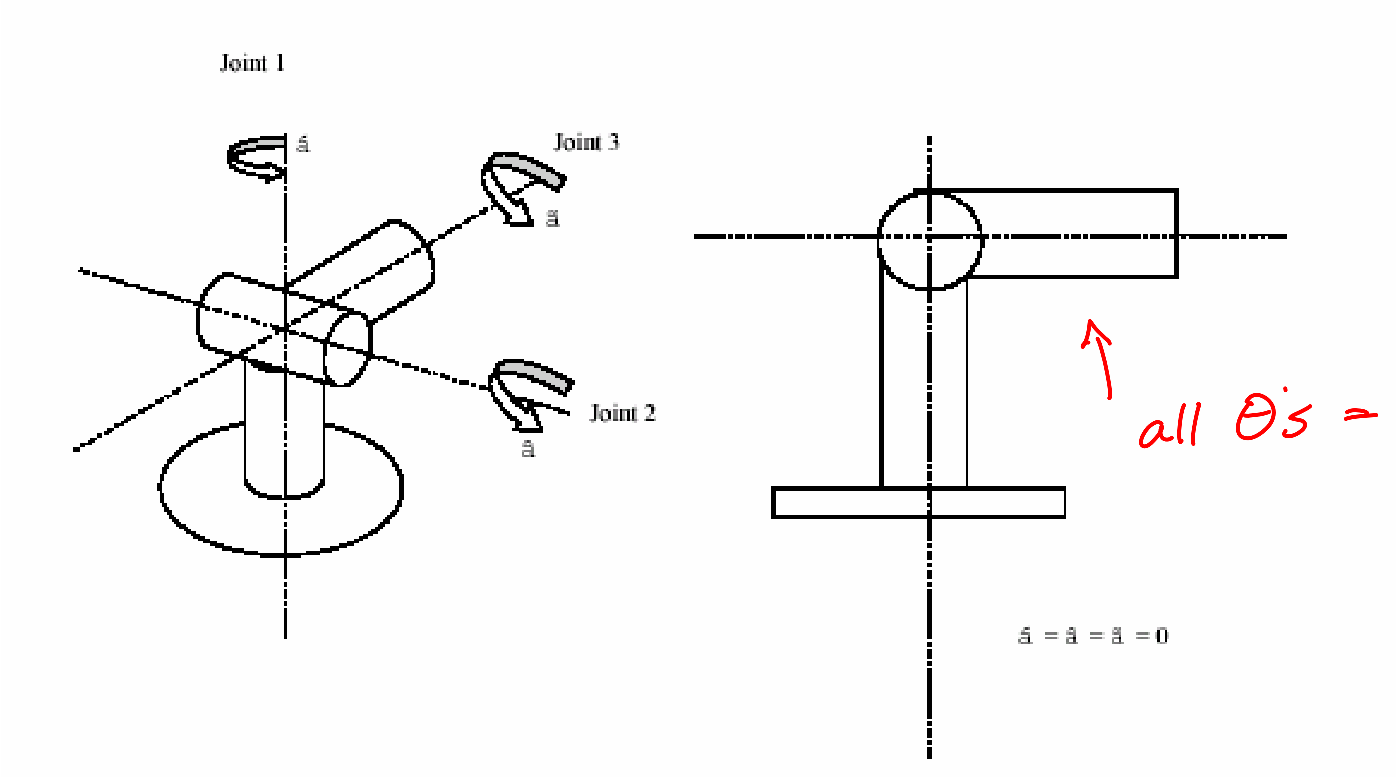
Central Topic - Inverse Manipulator Kinematics - Examples

- **Algebraic Solution** (closed form) –
  - Piepers Method (Continued)
    - Last three consecutive axes intersect at one point



Three consecutive Axes Intersect - wrist

- Consider a 3 DOF non-planar robot whose axes all intersect at a point.



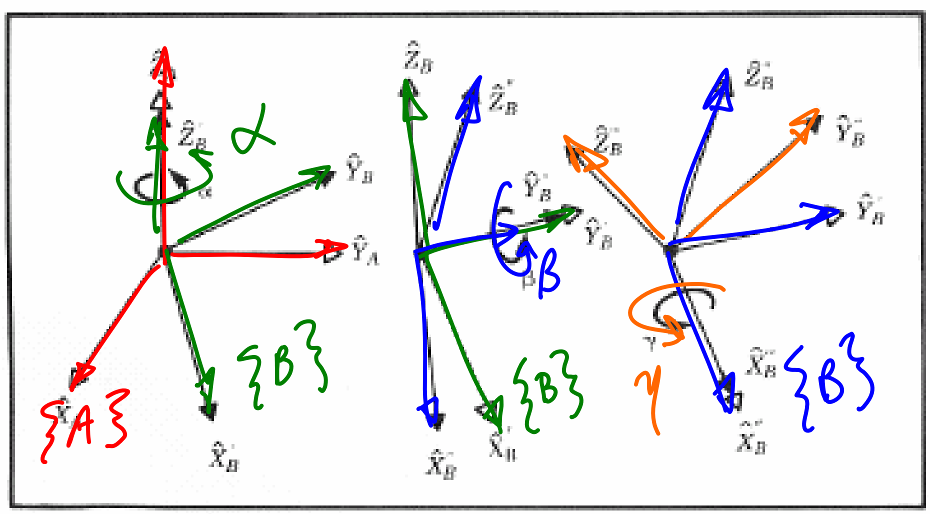
Mapping - Rotated Frames - Z-Y-X Euler Angles

Start with frame {B} coincident with a known reference frame {A}.

- Rotate frame {B} about $\hat{Z}_A$ by an angle α
- Rotate frame {B} about $\hat{Y}_B$ by an angle β
- Rotate frame {B} about $\hat{X}_B$ by an angle γ

(These three rotations are marked with a brace labelled **Euler Angles**.)

Note - *Each rotation is preformed about an axis of the the moving reference frame {B}, rather then a fixed reference frame {A}.*



Mapping - Rotated Frames - ZYX Euler Angles

$$
{}^{A}_{B}R_{X'Y'Z'}(\alpha,\beta,\gamma) = R_Z(\alpha)R_Y(\beta)R_X(\gamma) = \begin{bmatrix} c\alpha & -s\alpha & 0 \\ s\alpha & c\alpha & 0 \\ 0 & 0 & 1 \end{bmatrix} \begin{bmatrix} c\beta & 0 & s\beta \\ 0 & 1 & 0 \\ -s\beta & 0 & c\beta \end{bmatrix} \begin{bmatrix} 1 & 0 & 0 \\ 0 & c\gamma & -s\gamma \\ 0 & s\gamma & c\gamma \end{bmatrix}
$$

$$
{}^{A}_{B}R_{X'Y'Z'}(\alpha,\beta,\gamma) = \begin{bmatrix} c\alpha c\beta & c\alpha s\beta s\gamma - s\alpha c\gamma & c\alpha s\beta c\gamma + s\alpha s\gamma \\ s\alpha c\beta & s\alpha s\beta s\gamma + c\alpha c\gamma & s\alpha s\beta c\gamma - c\alpha s\gamma \\ -s\beta & c\beta s\gamma & c\beta c\gamma \end{bmatrix}
$$

$$
{}^{A}_{B}R_{X'Y'Z'}(\alpha,\beta,\gamma) = {}^{0}_{3}R = {}^{0}_{1}R\,{}^{1}_{2}R\,{}^{2}_{3}R
$$

Three consecutive Axes Intersect - wrist

- Because, in this example, our robot can perform no translations, we can write

$$
{}^{0}_{3}T = \begin{bmatrix} c\alpha c\beta & c\alpha s\beta s\gamma - s\alpha c\gamma & c\alpha s\beta c\gamma + s\alpha s\gamma & 0 \\ s\alpha c\beta & s\alpha s\beta s\gamma + c\alpha c\gamma & s\alpha s\beta c\gamma - c\alpha s\gamma & 0 \\ -s\beta & c\beta s\gamma & c\beta c\gamma & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix}
$$

- The above transform provides the solution to the forward kinematics.

Three consecutive Axes Intersect - wrist

- The inverse kinematics problem.
  - Given a particular rotation - Goal (again, this robot can perform no translations)
  - Solve: Find the Z-Y-X Euler angles

$$ {}^{0}_{3}T_{d} = \begin{bmatrix} & [R] & & 0 \\ & & & 0 \\ & & & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix} \qquad {}^{0}_{3}T(\alpha, \beta, \gamma) $$

Three consecutive Axes Intersect - wrist

ZYX Euler matrix

$\boxed{\cos\beta = 0}$

$$\underbrace{\begin{bmatrix} r11 & r12 & r13 & 0 \\ r21 & r22 & r23 & 0 \\ r31 & r32 & r33 & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix}}_{\text{Goal}} = \underbrace{\begin{bmatrix} c\alpha c\beta & c\alpha s\beta s\gamma - s\alpha c\gamma & c\alpha s\beta c\gamma + s\alpha s\gamma & 0 \\ s\alpha c\beta & s\alpha s\beta s\gamma + c\alpha c\gamma & s\alpha s\beta c\gamma - c\alpha s\gamma & 0 \\ -s\beta & c\beta s\gamma & c\beta c\gamma & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix}}_{\text{Direct Kinematics}}$$

α, β, γ

Forward

Three consecutive Axes Intersect - wrist

- Using elements r_{11} and r_{21}, we can solve for angle α

$$r_{11} = c\alpha c\beta$$

$$r_{21} = s\alpha c\beta$$

- when $\beta \neq \pm \frac{n\pi}{2}$ where n is an odd integer by using the Atan2 function we obtain

$$\alpha = \begin{cases} \text{Atan2}(r_{21}, r_{11}) \text{ when } c\beta \geq \mathbf{0} \\ \text{Atan2}(-r_{21}, -r_{11}) \text{ when } c\beta < \mathbf{0} \end{cases}$$

Three consecutive Axes Intersect - wrist

- Similarly, we find angle γ by

$$r_{32} = c\beta s\gamma$$
$$r_{33} = c\beta c\gamma$$

- when $\beta \neq \pm\frac{n\pi}{2}$ where n is an odd integer by using the Atan2 function we obtain

$$\gamma = \begin{cases} \mathrm{Atan2}(r_{32}, r_{33}) \text{ when } c\beta \geq \mathbf{0} \\ \mathrm{Atan2}(-r_{32}, -r_{33}) \text{ when } c\beta < \mathbf{0} \end{cases}$$

Three consecutive Axes Intersect - wrist

- The third angle, β , can be found from

$$r_{11}^2 + r_{21}^2 = c\beta^2\left(c\alpha^2 + s\alpha^2\right)$$

$$r_{31} = -s\beta$$

$$c\beta = \pm\sqrt{r11^2 + r21^2}$$

- Using the Atan2 function, we find

$$\beta = \mathrm{Atan2}\left(-r_{31}, \pm\sqrt{r_{11}^{\;2} + r_{21}^{\;2}}\right)$$

Three consecutive Axes Intersect - wrist

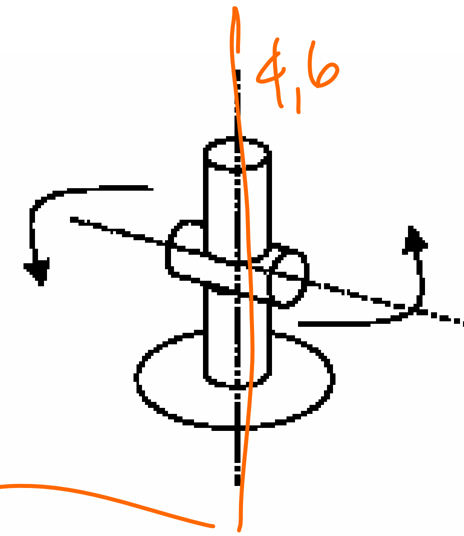
- Note: Two answers exist for angle β which will result in two answers each for angles α and γ .

$$\alpha = \begin{cases} \mathrm{Atan2}(r_{21}, r_{11}) \text{ when } c\beta \geq \mathbf{0} \\ \mathrm{Atan2}(-r_{21}, -r_{11}) \text{ when } c\beta < \mathbf{0} \end{cases}$$

$$\beta = \mathrm{atan2}\left(-r31, \pm\sqrt{r11^2 + r21^2}\right)$$

$$\gamma = \begin{cases} \mathrm{Atan2}(r_{32}, r_{33}) \text{ when } c\beta \geq \mathbf{0} \\ \mathrm{Atan2}(-r_{32}, -r_{33}) \text{ when } c\beta < \mathbf{0} \end{cases}$$

Three consecutive Axes Intersect - wrist



- What do we do if $\beta = 90^o$?
- This is troublesome because $\cos(90^o) = 0$.
- Applying the difference of angles formula, we find:

$$\begin{bmatrix} r11 & r12 & r13 & 0 \\ r21 & r22 & r23 & 0 \\ r31 & r32 & r33 & 0 \\ 1 & 1 & 1 & 1 \end{bmatrix} = \begin{bmatrix} 0 & s(\gamma-\alpha) & c(\gamma-\alpha) & 0 \\ 0 & c(\gamma-\alpha) & s(\gamma-\alpha) & 0 \\ -1 & 0 & 0 & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix}$$

- We are left with $(\gamma - \alpha)$ for every case. This means we can't solve for either, just their difference.

Three consecutive Axes Intersect - wrist

- One solution is to define two cases such that

$$\gamma - \alpha = \text{Atan2}(r_{12}, r_{22}) \quad \text{if} \quad \beta = 90^0$$

$$\gamma + \alpha = \text{Atan2}(r_{12}, r_{22}) \quad \text{if} \quad \beta = -90^0$$

Three consecutive Axes Intersect - wrist

- Unfortunately, while this seems like a simple solution, it is troublesome in practice because α is never exactly zero. This leads to singularity problems
- For this example, the singular case results in the capability for self-rotation. That is, the middle link can rotate while the end effector's orientation never changes.