Important concepts, symbols, and equations

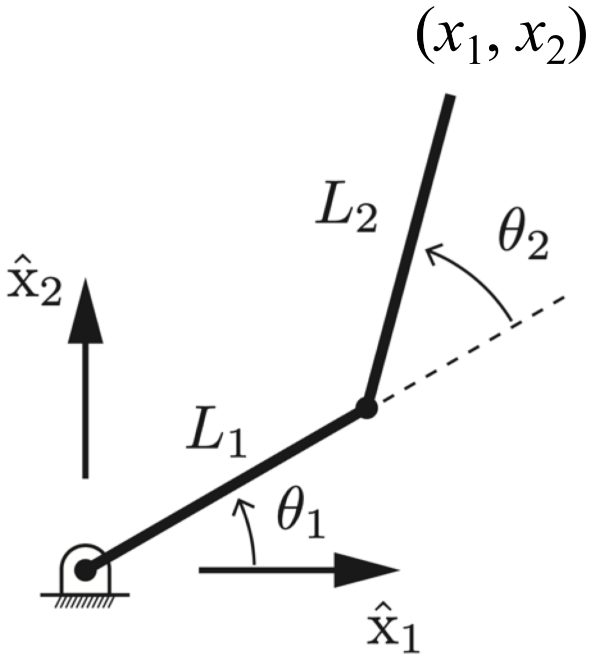
- "Geometric" forward kinematics

$$\theta(t) \in \mathbb{R}^n, \;\; \mathcal{X}(t) = T_{sb}(\theta(t)) \in SE(3) \text{ via PoE}$$

- "Minimum coordinate" forward kinematics

$$\theta(t) \in \mathbb{R}^n, \;\; x(t) = f(\theta(t)) \in \mathbb{R}^m$$

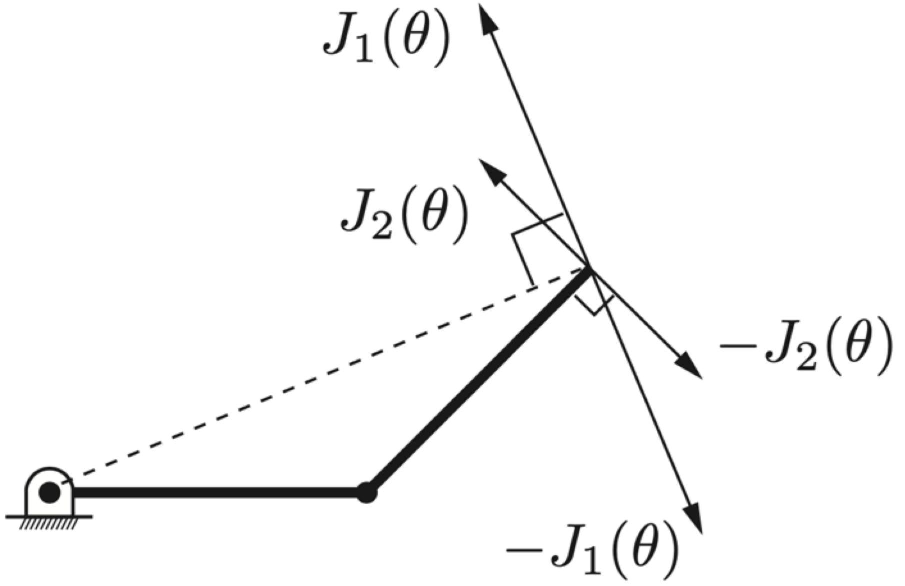
$$\begin{aligned} x_1 &= L_1 \cos\theta_1 + L_2 \cos(\theta_1 + \theta_2) \\ x_2 &= L_1 \sin\theta_1 + L_2 \sin(\theta_1 + \theta_2) \end{aligned}$$



Important concepts, symbols, and equations (cont.)

$$\dot{x} = \frac{\partial f(\theta)}{\partial \theta}\frac{d\theta(t)}{dt} = \underbrace{\frac{\partial f(\theta)}{\partial \theta}}\dot{\theta}$$
$$= J(\theta)\dot{\theta}$$

(coordinate)
Jacobian

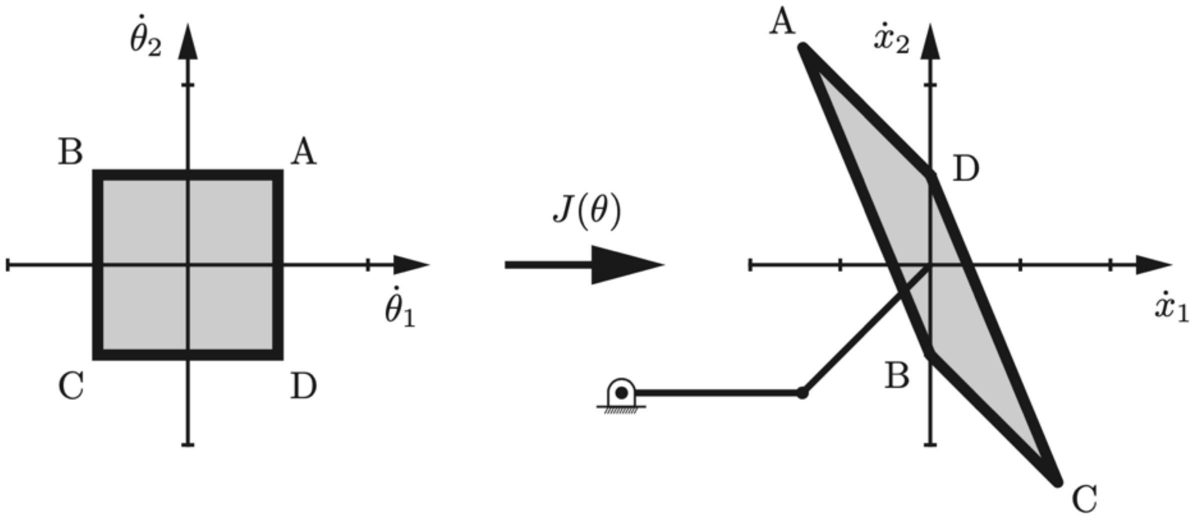


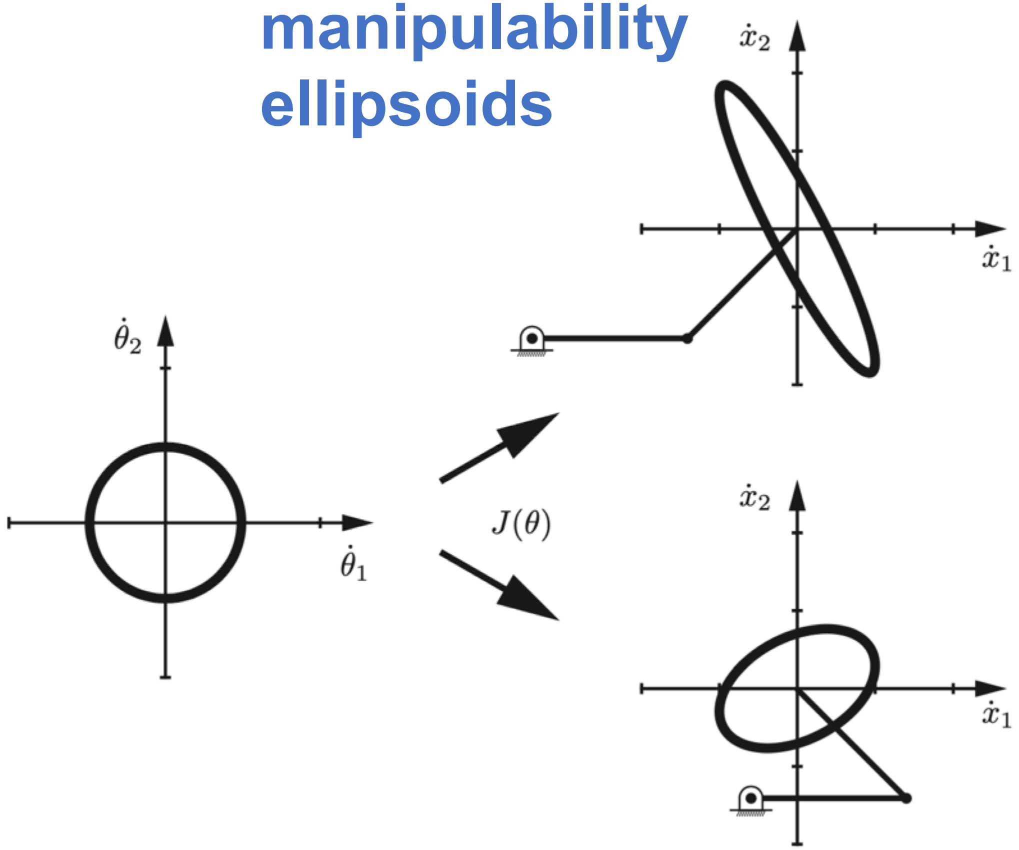
$$\dot{x} = [\, J_1(\theta) \;\; J_2(\theta) \,] \; [\, \dot{\theta}_1 \;\; \dot{\theta}_2 \,]^{\mathrm{T}} = J_1(\theta)\,\dot{\theta}_1 + J_2(\theta)\,\dot{\theta}_2$$

Column i is the end-effector velocity when $\dot{\theta}_i = 1$.

<u>Important concepts, symbols, and equations</u> (cont.)

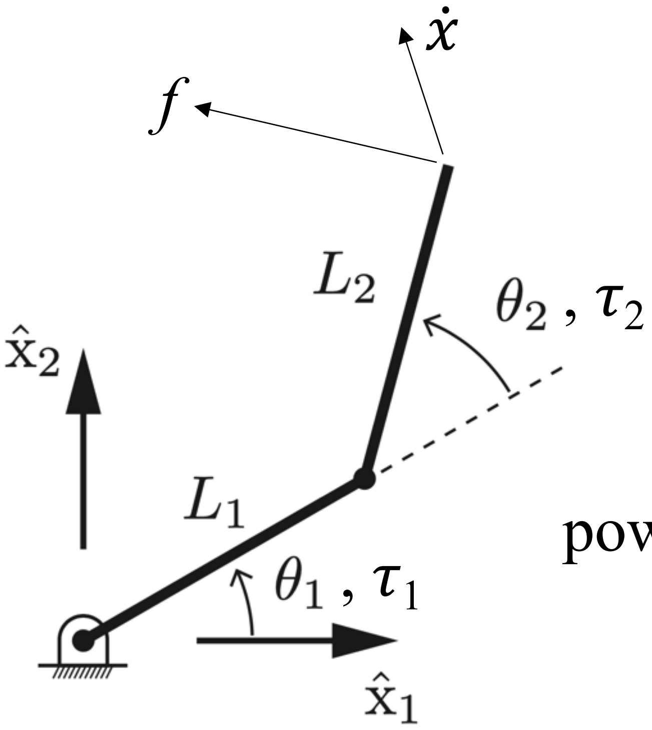
manipulability ellipsoids





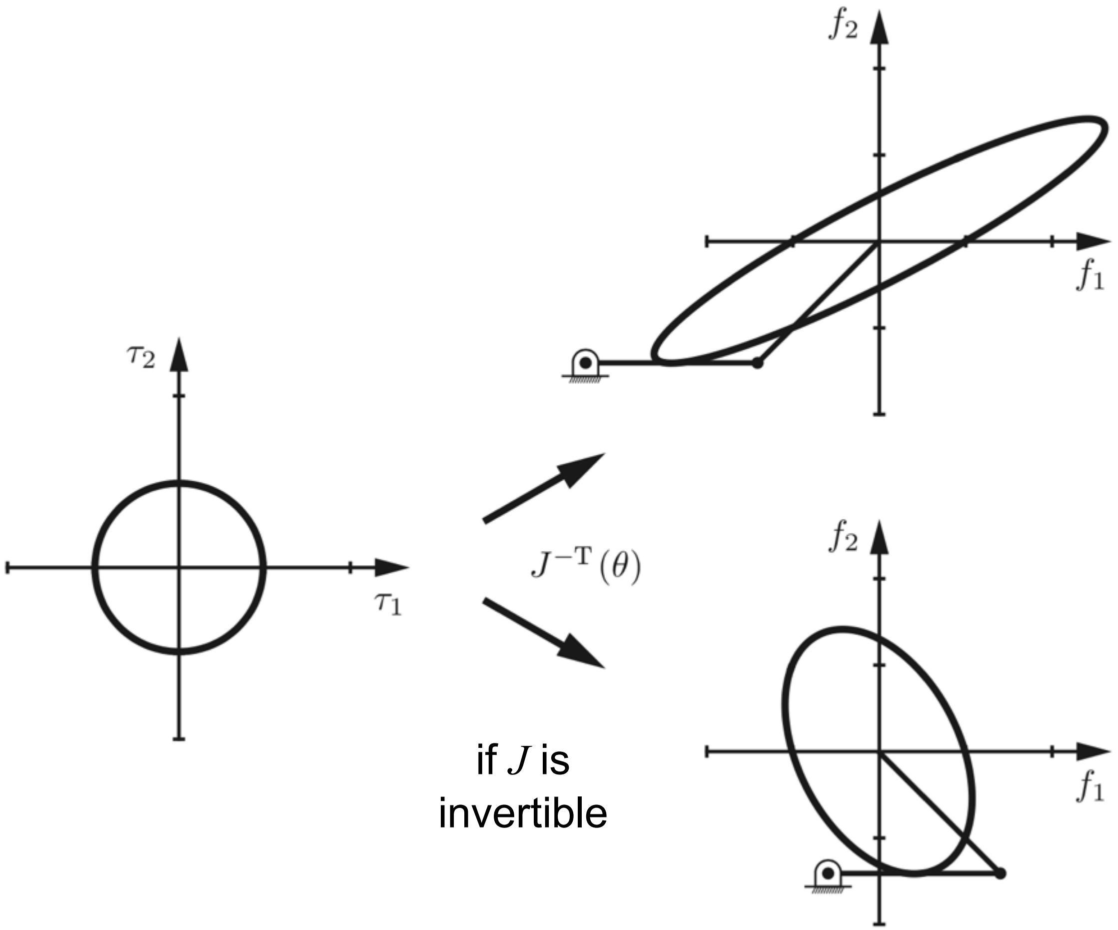
mapping joint velocity limits to end-effector velocity limits

Important concepts, symbols, and equations (cont.)



$$\text{power} = \dot{\theta}^{T} \tau = \dot{x}^{T} f$$
$$\dot{\theta}^{T} \tau = (J\,\dot{\theta})^{T} f$$
$$\dot{\theta}^{T} \tau = \dot{\theta}^{T} J^{T} f$$

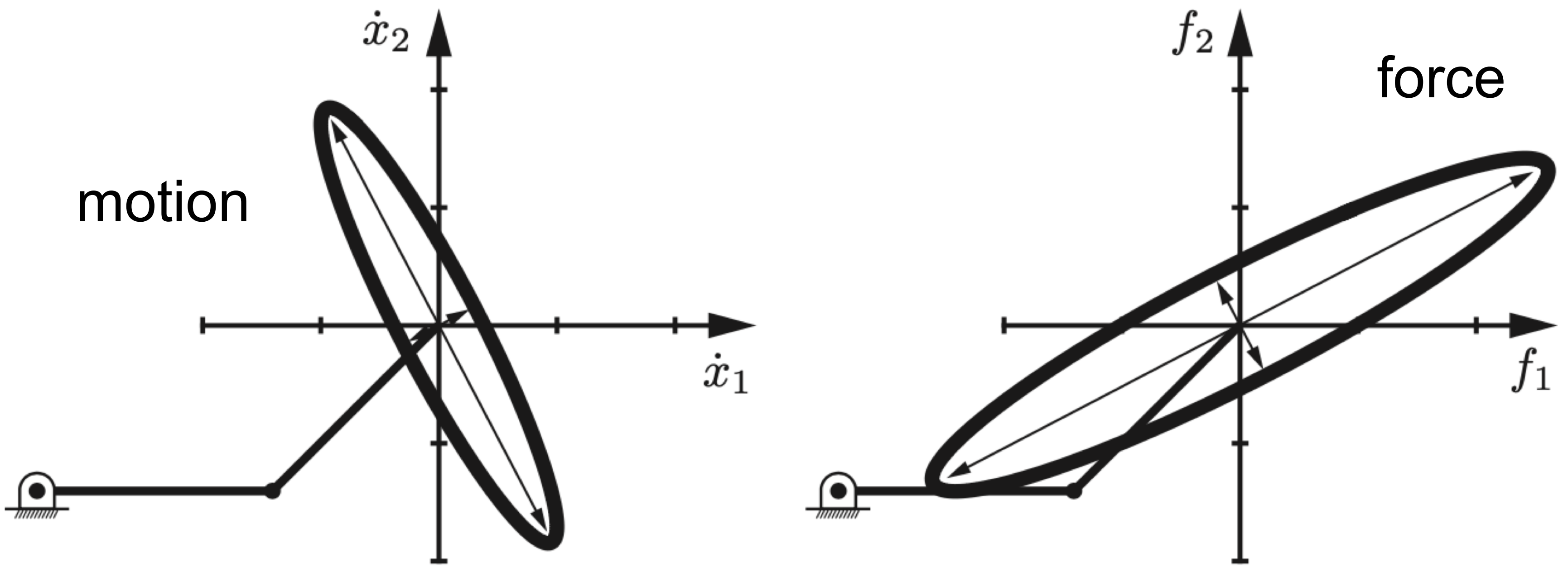
$$\boxed{\tau = J^{T} f}$$



Important concepts, symbols, and equations (cont.)

A configuration θ is **singular** if $J(\theta)$ loses rank.

- e-e motion capability becomes zero in one or more directions
- e-e can resist infinite force in one or more directions



approaching a singularity...

Important concepts, symbols, and equations (cont.)

- **Space Jacobian**

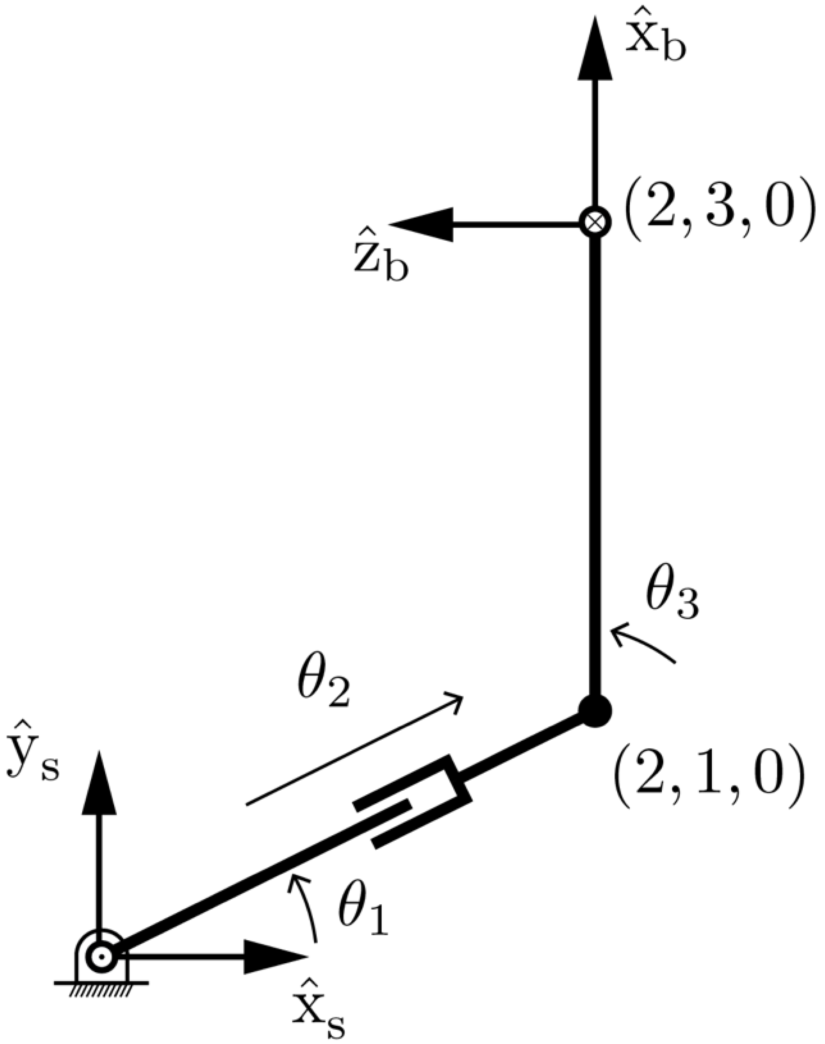
$$\mathcal{V}_s = J_s(\theta)\dot{\theta} \quad \text{where} \left\{ \begin{array}{l} J_{s1} = \mathcal{S}_1 \\ J_{si}(\theta) = \mathrm{Ad}_{e^{[\mathcal{S}_1]\theta_1}\cdots e^{[\mathcal{S}_{i-1}]\theta_{i-1}}}(\mathcal{S}_i) \end{array} \right. \quad i = 2, \ldots, n$$

- **Body Jacobian**

$$\mathcal{V}_b = J_b(\theta)\dot{\theta} \quad \text{where} \left\{ \begin{array}{l} J_{bi}(\theta) = \mathrm{Ad}_{e^{-[\mathcal{B}_n]\theta_n}\cdots e^{-[\mathcal{B}_{i+1}]\theta_{i+1}}}(\mathcal{B}_i) \quad i = 1, \ldots, n-1 \\ J_{bn} = \mathcal{B}_n \end{array} \right.$$

$$\begin{aligned} J_s(\theta) &= [\mathrm{Ad}_{T_{sb}}]J_b(\theta) \\ J_b(\theta) &= [\mathrm{Ad}_{T_{bs}}]J_s(\theta) \end{aligned}$$

Column i is the end-effector twist when $\dot{\theta}_i = 1$.



$J_s(\theta) =$

$J_b(\theta) =$