Questions

1. Given Euler angles $\theta_x, \theta_y, \theta_z$, the corresponding rotation matrix is given by

$$R = R_x R_y R_z = \begin{pmatrix} C_y C_z & -C_y S_z & S_y \\ S_x S_y C_z + C_x S_z & -S_x S_y S_z + C_x C_z & -S_x C_y \\ -C_x S_y C_z + S_x S_z & C_x S_y S_z + S_x C_z & C_x C_y \end{pmatrix}$$

where

$$C_x = \cos \theta_x$$
 $S_x = \sin \theta_x$
 $C_y = \cos \theta_y$ $S_y = \sin \theta_y$
 $C_z = \cos \theta_z$ $S_z = \sin \theta_z$

Consider the matrix

$$R = \begin{pmatrix} 0 & 0 & 1\\ \frac{\sqrt{2}}{2} & \frac{\sqrt{2}}{2} & 0\\ -\frac{\sqrt{2}}{2} & \frac{\sqrt{2}}{2} & 0 \end{pmatrix}$$

Find angles $\theta_x, \theta_y, \theta_z$ such that $R = R_x R_y R_z$. Are there more choices of $\theta_x, \theta_y, \theta_z$?

Solution: One possible solution is $(45^{\circ}, 90^{\circ}, 0^{\circ})$. This is not the only possibility.

2. Given an axis \mathbf{r} (unit vector) and an angle θ , the matrix representing the rotation of θ around \mathbf{r} is given by

$$R_{\mathbf{r}\theta} = \begin{pmatrix} tx^2 + c & txy - sz & txz + sy \\ txy + sz & ty^2 + c & tyz - sx \\ txz - sy & tyz + sx & tz^2 + c \end{pmatrix}$$

where

$$\mathbf{r} = (x, y, z)$$

$$c = \cos \theta$$

$$s = \sin \theta$$

$$t = 1 - \cos \theta$$

Consider the rotation matrix

$$R = \begin{pmatrix} 0 & 0 & 1 \\ 0 & -1 & 0 \\ 1 & 0 & 0 \end{pmatrix}$$

Determine the rotation angle and rotation axis.

Solution: 180° , $(1,0,1)^{T}$ (your answer may differ by a positive scaling factor)

3. Determine the quaternion that corresponds to rotation around the axis $(-1, -2, -2)^T$ with $\theta = 270^{\circ}$.

Solution:
$$\left(-\frac{\sqrt{2}}{2}, -\frac{\sqrt{2}}{6}, -\frac{\sqrt{2}}{3}, -\frac{\sqrt{2}}{3}\right)$$

4. Find the quaternion q that corresponds to rotation around the axis (1,1,0) with 90° . Consider the point (1,1,1). Let $p_1=(0,1,1,1)$ be the corresponding quaternion. Calculate qp_1q^{-1} . Let $p_2=(0,1,1,0)$. Argue that qp_2q^{-1} equals p_2 . Show this by performing the exact calculations.

Solution: $(\frac{\sqrt{2}}{2}, \frac{1}{2}, \frac{1}{2}, 0)$