变化前

腕部数据（left):

[[ 0. 0. -1. -0.753]

[-1. 0. 0. 0.191]

[ 0. 1. 0. 0.117]

[ 0. 0. 0. 1. ]]

变化中

腕部数据（left):

[[-1. 0. 0. 0.191]

[ 0. 0. 1. 0.753]

[ 0. 1. 0. 0.117]

[ 0. 0. 0. 1. ]]

变化后

腕部数据（left):

[[-1. 0. 0. 0.191]

[ 0. 1. 0. 0.117]

[ 0. 0. -1. -0.753]

[ 0. 0. 0. 1. ]]

仿真中实际的位置

[0.2,0.753,1.22]

[0.189,-0.77,-0.912,0.355]

quaternion = [0.383, 0.472, 0.090, 0.788]

Original Rotation Matrix:

[[-0.50413964 -0.68996221 0.5194183 -0.753 ]

[ 0.53754618 0.22003832 0.81401919 0.191 ]

[-0.67593441 0.68959066 0.25995652 0.117 ]

[ 0. 0. 0. 1. ]]

[[ 0.53754618 0.22003832 0.81401919]

[ 0.50413964 0.68996221 -0.5194183 ]

[-0.67593441 0.68959066 0.25995652]]

变化前

腕部数据（left): [[ 0. 0. -1. -0.5]

[-1. 0. 0. 0.3]

[ 0. 1. 0. 0.3]

[ 0. 0. 0. 1. ]]

变化中

腕部数据（left): [[-1. 0. 0. 0.3]

[ 0. 0. 1. 0.5]

[ 0. 1. 0. 0.3]

[ 0. 0. 0. 1. ]]

变化后

腕部数据（left): [[-1. 0. 0. 0.3]

[ 0. 1. 0. 0.3]

[ 0. 0. -1. -0.5]

[ 0. 0. 0. 1. ]]

仿真中的数据

[0.344,0.5.1.3]

[1,0,0.1,0]

变化前

腕部数据（left):

[[-2.88888659e-15 -1.04930118e-15 -1.00000000e+00 -5.00000000e-01]

[ 9.39692621e-01 3.42020143e-01 -3.07354755e-15 3.00000000e-01]

[ 3.42020143e-01 -9.39692621e-01 -2.03682837e-18 3.00000000e-01]

[ 0.00000000e+00 0.00000000e+00 0.00000000e+00 1.00000000e+00]]

变化中

腕部数据（left):

[[ 9.39692621e-01 3.42020143e-01 -3.07354755e-15 3.00000000e-01]

[ 2.88888659e-15 1.04930118e-15 1.00000000e+00 5.00000000e-01]

[ 3.42020143e-01 -9.39692621e-01 -2.03682837e-18 3.00000000e-01]

[ 0.00000000e+00 0.00000000e+00 0.00000000e+00 1.00000000e+00]]

变化后

腕部数据（left):

[[ 9.39692621e-01 3.42020143e-01 -3.07354755e-15 3.00000000e-01]

[ 3.42020143e-01 -9.39692621e-01 -2.03682837e-18 3.00000000e-01]

[-2.88888659e-15 -1.04930118e-15 -1.00000000e+00 -5.00000000e-01]

[ 0.00000000e+00 0.00000000e+00 0.00000000e+00 1.00000000e+00]]

滤波后的手腕信息

[[ 9.39698664e-01 3.41990039e-01 -3.03882462e-03 3.00076395e-01]

[ 2.85373597e-03 1.04435414e-03 9.99995383e-01 5.00913441e-01]

[ 3.41991634e-01 -9.39702997e-01 5.42890956e-06 2.99998403e-01]

[ 0.00000000e+00 0.00000000e+00 0.00000000e+00 1.00000000e+00]]

变化前

腕部数据（left):

[[-0.24613998 ,0.96672967 ,-0.06963371 ,-0.34991334]

[ 0.96870006 ,0.24775365 ,0.01543782 , 0.28252333]

[ 0.0321762 ,-0.06365431, -0.99745317 ,0.38583692]

[ 0. 0. 0. 1. ]]