2D Rigid-Body Motions and Rotation Matrices

CS 6301 Special Topics: Introduction to Robot Manipulation and Navigation

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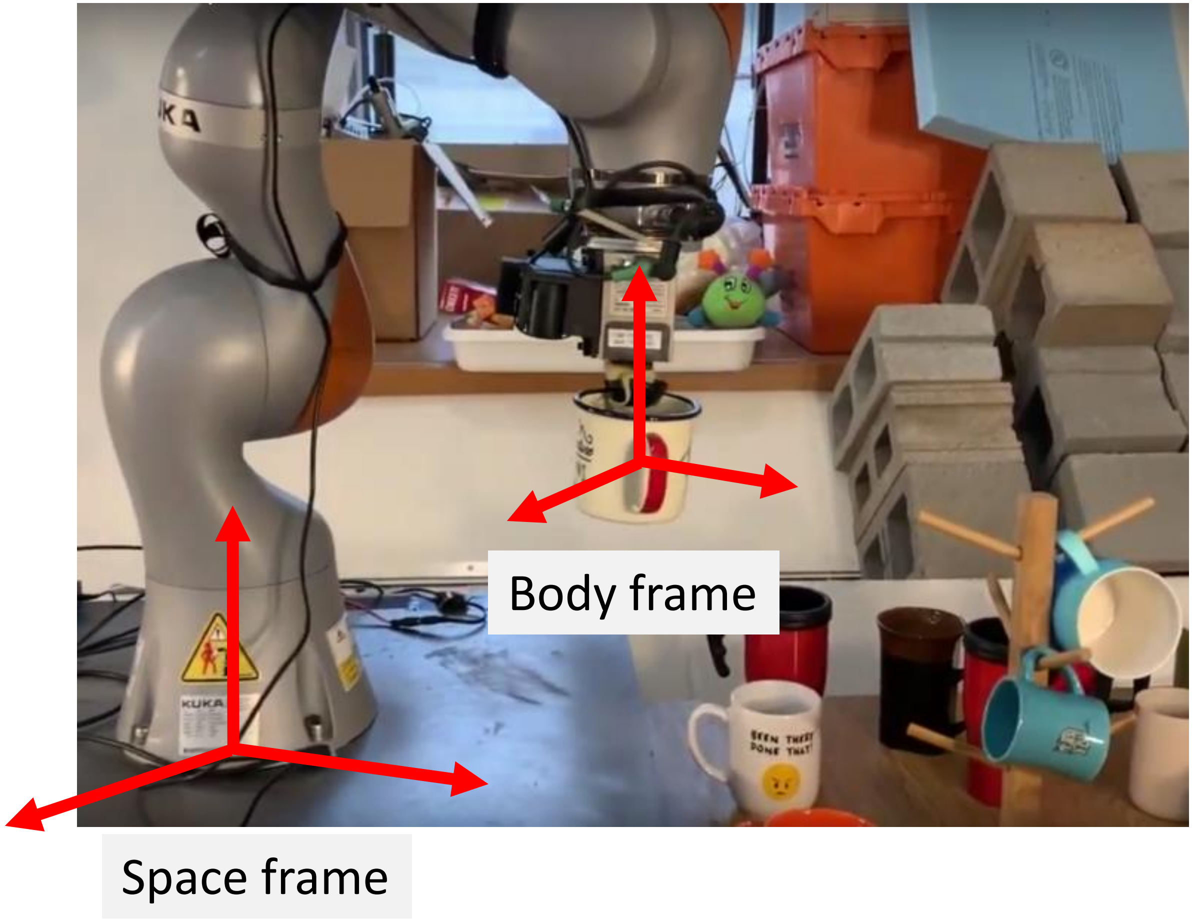
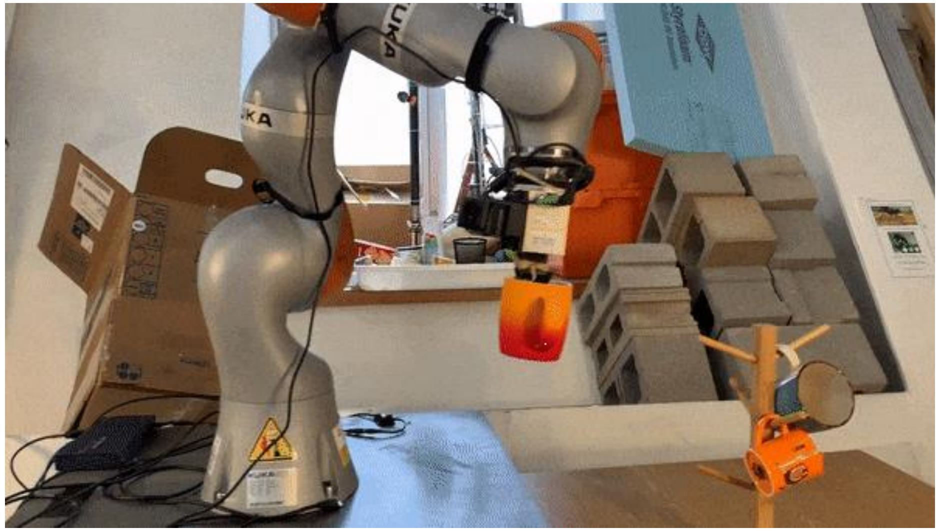
Rigid-Body Motions



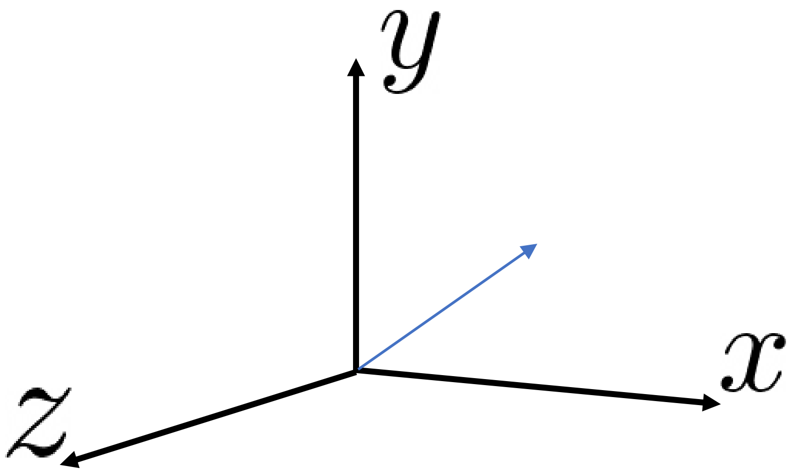


https://venturebeat.com/ai/mit-csail-refines-picker-robots-ability-to-handle-new-objects/

Vectors and Reference Frames

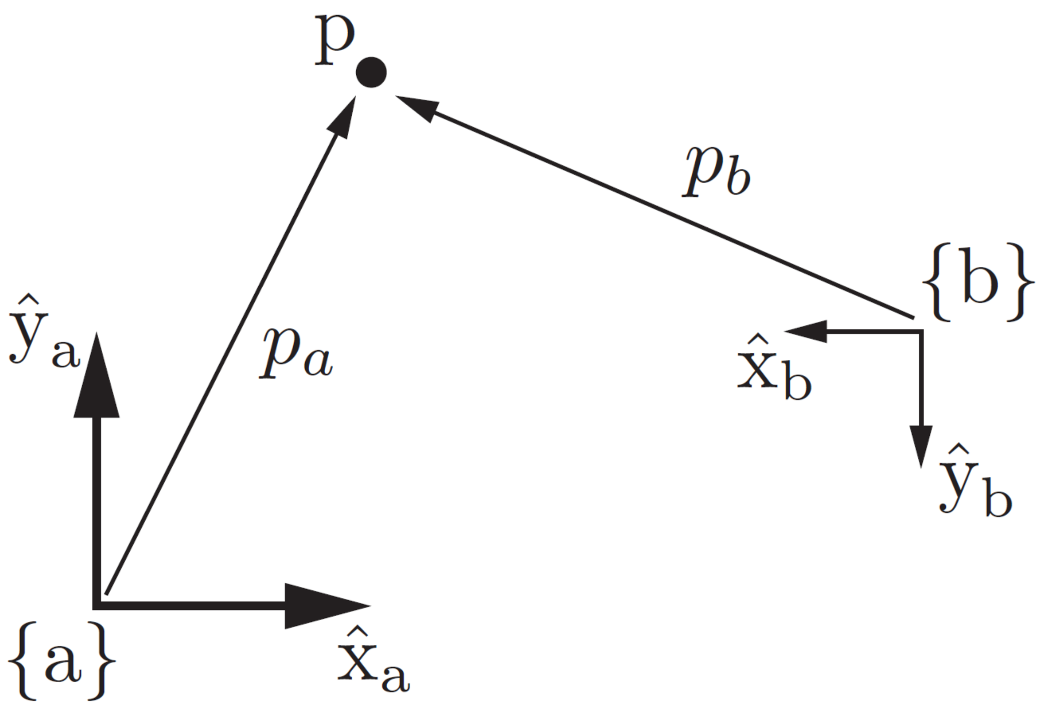
- A **free vector**: a geometric quantity with a length and a direction
  - An arrow in $\mathbb{R}^n$, not rooted anywhere
  - E.g., a linear velocity

- A free vector in a reference frame
  - The base of the arrow at the origin
  - Coordinates in the reference frame $v \in \mathbb{R}^n$
  - Coordinates change with reference frames
  - The underlying free vector does not change (coordinate free)



Points

- A point in space can be represented as a vector



Reference frame b

Reference frame a

More about Reference Frames

- A reference frame can be attached anywhere

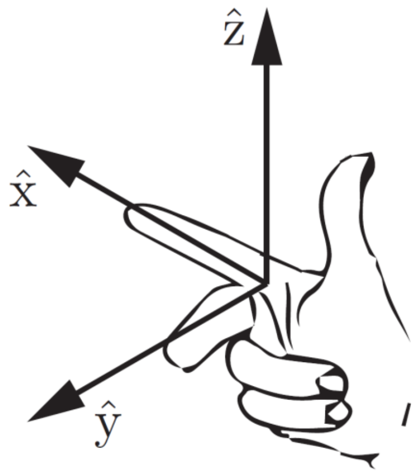
- Different reference frames result in different representations of the space and objects, but the underlying geometry is the same

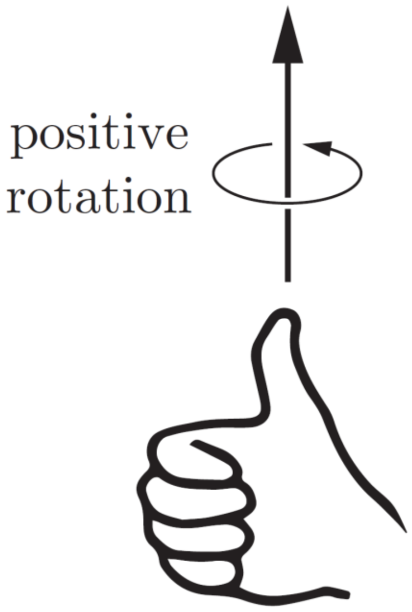
- Always assume one stationary **fixed frame** or **space frame** {s}
  - E.g., a corner of a room

- **Body frame** {b} is the stationary frame coincident with the body-attached frame at any instance
  - E.g., origin on the center of mass of the body

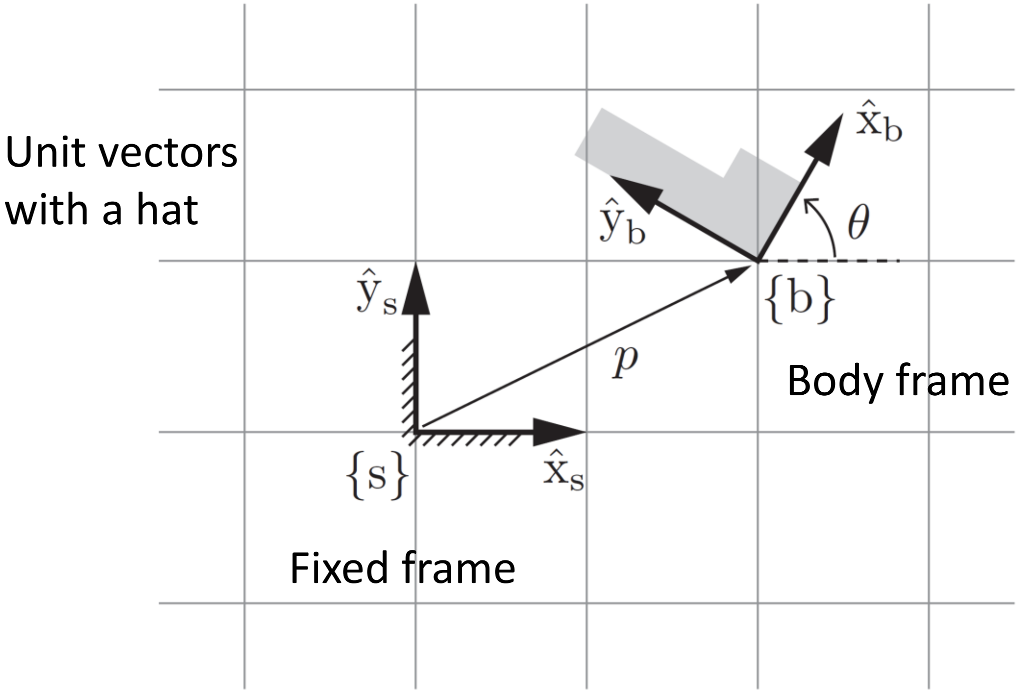
More about Reference Frames

- All frames in this course are stationary
- All frames in this course are right-handed





Rigid-Body Motions in the Plane



- Configuration of the planer body
  - Position and orientation with respect to the fixed frame
- Body frame origin in the fixed frame

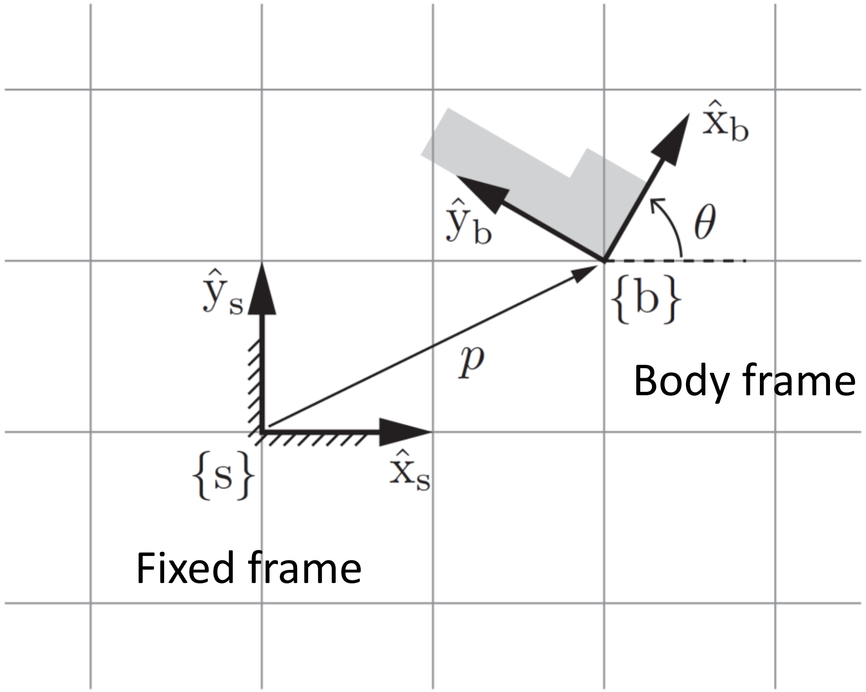
$$p = p_x \hat{x}_s + p_y \hat{y}_s$$

$$p = (p_x, p_y)$$ Vector form

- Rotation angle θ
- Directions of the body frame

$$\begin{aligned} \hat{x}_b &= \cos\theta\, \hat{x}_s + \sin\theta\, \hat{y}_s, \\ \hat{y}_b &= -\sin\theta\, \hat{x}_s + \cos\theta\, \hat{y}_s \end{aligned}$$

Rigid-Body Motions in the Plane



- The two axes of the body frame in {s}

$$P = [\hat{x}_b \;\; \hat{y}_b] = \begin{bmatrix} \cos\theta & -\sin\theta \\ \sin\theta & \cos\theta \end{bmatrix}$$

Write as column vectors

Rotation matrix

1DOF

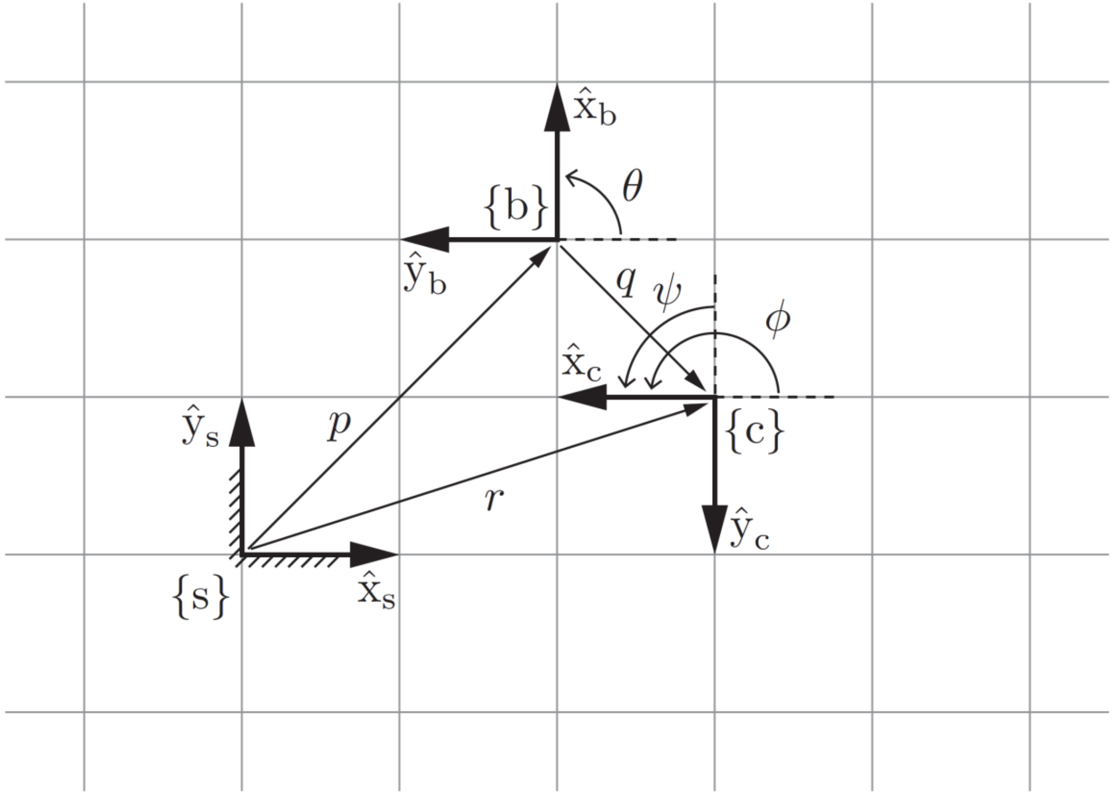
$$p = \begin{bmatrix} p_x \\ p_y \end{bmatrix}$$

Translation

$$(P, p)$$

specifies the orientation and position of {b} relative to {s}

Rigid-Body Motions in the Plane



- {c} in {s}

$$r = \begin{bmatrix} r_x \\ r_y \end{bmatrix}, \qquad R = \begin{bmatrix} \cos\phi & -\sin\phi \\ \sin\phi & \cos\phi \end{bmatrix}$$

- {c} in {b}

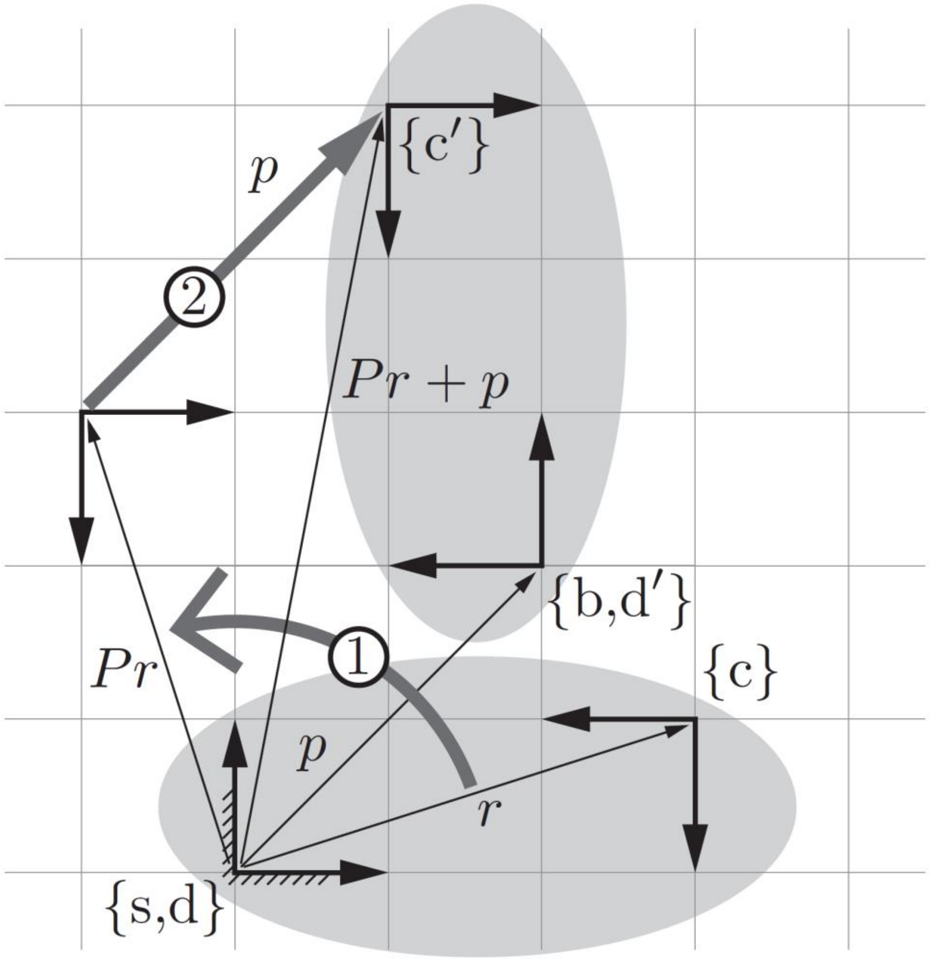
$$q = \begin{bmatrix} q_x \\ q_y \end{bmatrix}, \qquad Q = \begin{bmatrix} \cos\psi & -\sin\psi \\ \sin\psi & \cos\psi \end{bmatrix}$$

- With {b} in {s} and {c} in {b}

$$R = PQ \quad \text{(convert } Q \text{ to the \{s\} frame)}$$

$$r = Pq + p \quad \text{(convert } q \text{ to the \{s\} frame and vector-sum with } p\text{)}$$

Rigid-Body Motions in the Plane



- Two frames attached to a rigid body {d} {c}
- Initially, {d} = {s}, {c} in {s} by (R, r)
- Now, {d} move to {b} (P, p) in $\{s\}$
- Where dose {c} end up?

$$R' = PR,$$
$$r' = Pr + p.$$

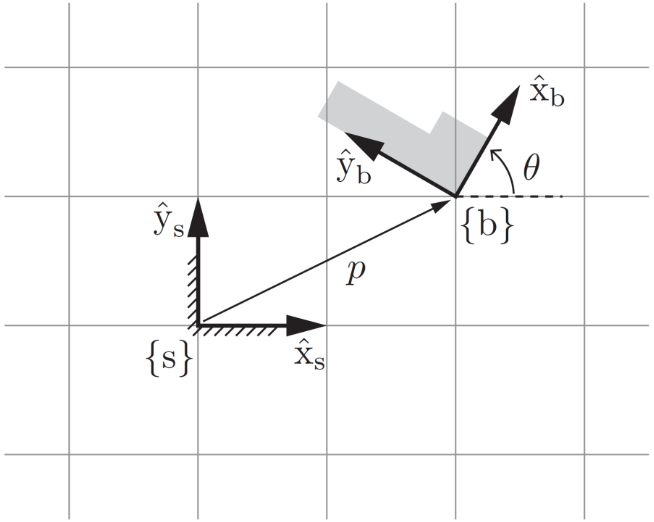
(P, p) is expressed in the same frame as (R, r)

not viewed as a change of coordinates

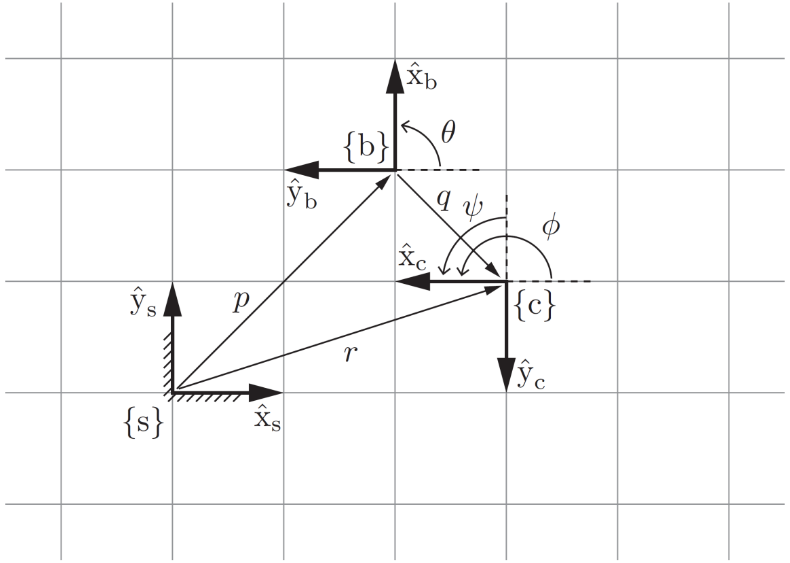
Known as a rigid-body motion

A Rotation Matrix-Vector Pair (P, p)

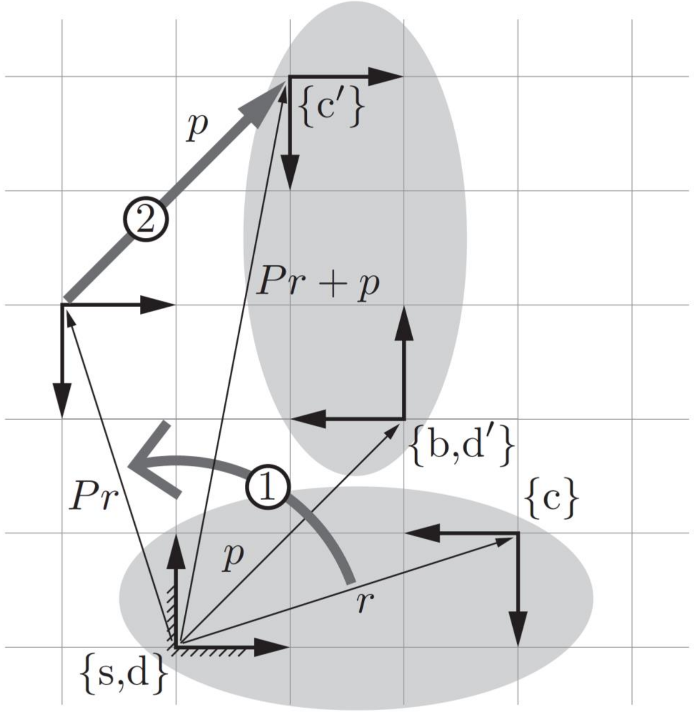
- Represent a configuration of a rigid body in {s}



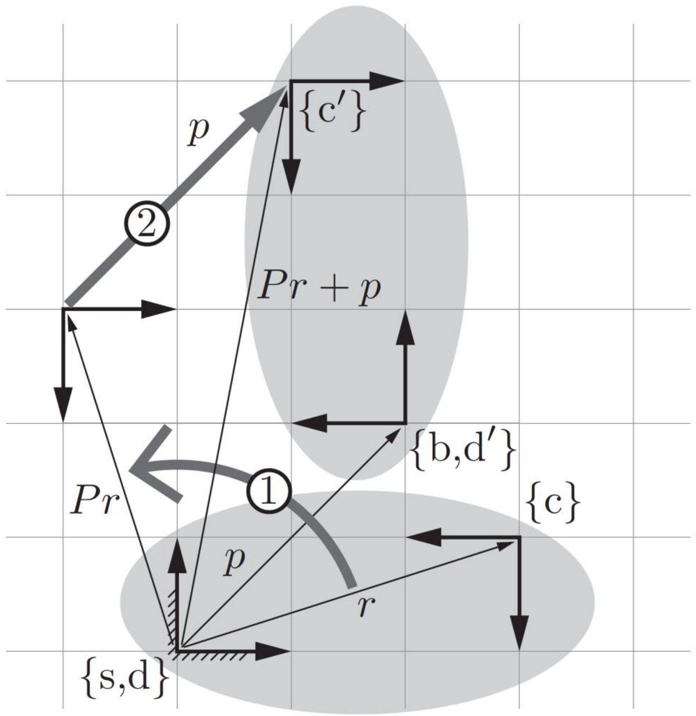
- Change the reference frame



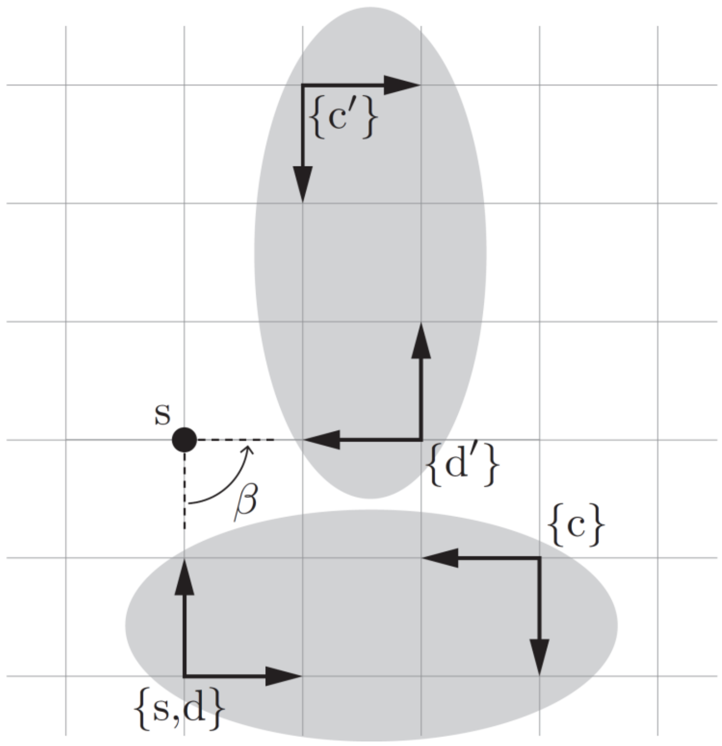
- Displace a vector or a frame



Rigid-Body Motions in the Plane



Rotation followed by translation



Rotation about a fixed point s by β **Screw motion**

three screw coordinates (β, s_x, s_y)

Rigid-Body in 3D

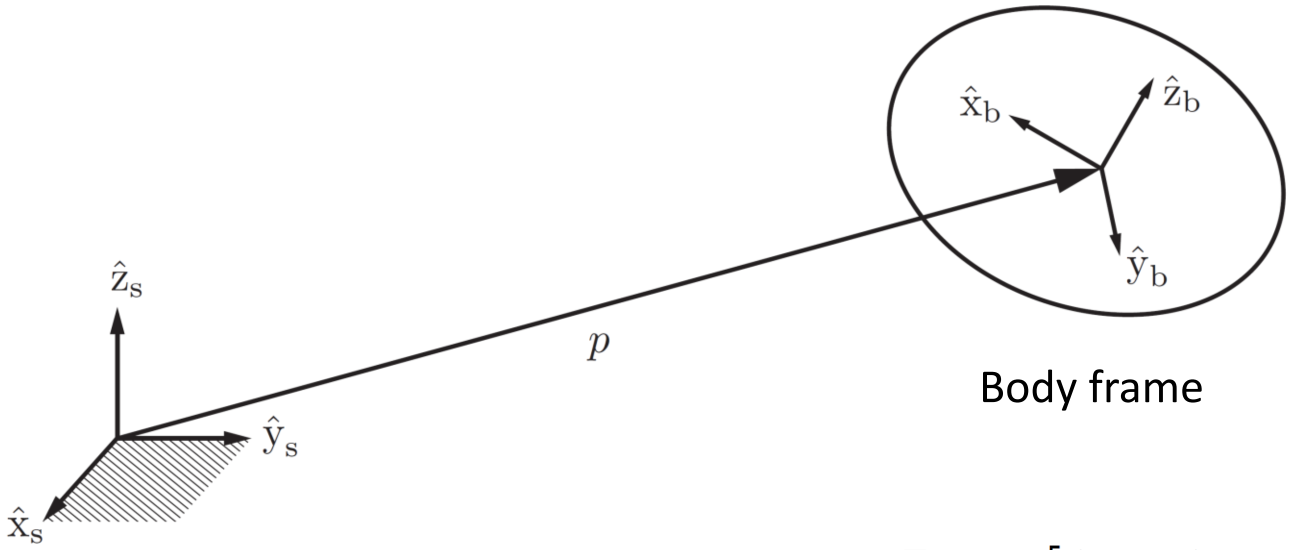
$$p = \begin{bmatrix} p_1 \\ p_2 \\ p_3 \end{bmatrix}$$

- Origin of the body frame

$$p = p_1\hat{\mathrm{x}}_{\mathrm{s}} + p_2\hat{\mathrm{y}}_{\mathrm{s}} + p_3\hat{\mathrm{z}}_{\mathrm{s}}$$

- Axes of the body frame

$$\begin{aligned} \hat{\mathrm{x}}_{\mathrm{b}} &= r_{11}\hat{\mathrm{x}}_{\mathrm{s}} + r_{21}\hat{\mathrm{y}}_{\mathrm{s}} + r_{31}\hat{\mathrm{z}}_{\mathrm{s}}, \\ \hat{\mathrm{y}}_{\mathrm{b}} &= r_{12}\hat{\mathrm{x}}_{\mathrm{s}} + r_{22}\hat{\mathrm{y}}_{\mathrm{s}} + r_{32}\hat{\mathrm{z}}_{\mathrm{s}}, \\ \hat{\mathrm{z}}_{\mathrm{b}} &= r_{13}\hat{\mathrm{x}}_{\mathrm{s}} + r_{23}\hat{\mathrm{y}}_{\mathrm{s}} + r_{33}\hat{\mathrm{z}}_{\mathrm{s}}. \end{aligned}$$



Body frame

Fixed frame

$$R = [\hat{\mathrm{x}}_{\mathrm{b}} \ \ \hat{\mathrm{y}}_{\mathrm{b}} \ \ \hat{\mathrm{z}}_{\mathrm{b}}] = \begin{bmatrix} r_{11} & r_{12} & r_{13} \\ r_{21} & r_{22} & r_{23} \\ r_{31} & r_{32} & r_{33} \end{bmatrix}$$

Write as column vectors

Rotation matrix

Rotation Matrix

- Unit norm condition

$$\begin{aligned} r_{11}^2 + r_{21}^2 + r_{31}^2 &= 1, \\ r_{12}^2 + r_{22}^2 + r_{32}^2 &= 1, \\ r_{13}^2 + r_{23}^2 + r_{33}^2 &= 1. \end{aligned}$$

$$R = [\hat{\mathrm{x}}_{\mathrm{b}} \;\; \hat{\mathrm{y}}_{\mathrm{b}} \;\; \hat{\mathrm{z}}_{\mathrm{b}}] = \begin{bmatrix} r_{11} & r_{12} & r_{13} \\ r_{21} & r_{22} & r_{23} \\ r_{31} & r_{32} & r_{33} \end{bmatrix}$$

- Orthogonality condition $\hat{\mathrm{x}}_{\mathrm{b}} \cdot \hat{\mathrm{y}}_{\mathrm{b}} = \hat{\mathrm{x}}_{\mathrm{b}} \cdot \hat{\mathrm{z}}_{\mathrm{b}} = \hat{\mathrm{y}}_{\mathrm{b}} \cdot \hat{\mathrm{z}}_{\mathrm{b}} = 0$

$$\begin{aligned} r_{11}r_{12} + r_{21}r_{22} + r_{31}r_{32} &= 0, \\ r_{12}r_{13} + r_{22}r_{23} + r_{32}r_{33} &= 0, \\ r_{11}r_{13} + r_{21}r_{23} + r_{31}r_{33} &= 0. \end{aligned}$$

Rotation Matrix

- Orthogonal matrix $R^{\mathrm{T}}R = I$
- Right-handed $\hat{\mathrm{x}}_{\mathrm{b}} \times \hat{\mathrm{y}}_{\mathrm{b}} = \hat{\mathrm{z}}_{\mathrm{b}}$
- Left-handed $\hat{\mathrm{x}}_{\mathrm{b}} \times \hat{\mathrm{y}}_{\mathrm{b}} = -\hat{\mathrm{z}}_{\mathrm{b}}$

$$R = [\hat{\mathrm{x}}_{\mathrm{b}} \quad \hat{\mathrm{y}}_{\mathrm{b}} \quad \hat{\mathrm{z}}_{\mathrm{b}}] = \begin{bmatrix} r_{11} & r_{12} & r_{13} \\ r_{21} & r_{22} & r_{23} \\ r_{31} & r_{32} & r_{33} \end{bmatrix}$$

Determinant of a 3x3 matrix M

$$\det M = a^{\mathrm{T}}(b \times c) = c^{\mathrm{T}}(a \times b) = b^{\mathrm{T}}(c \times a)$$

$$\det R = \pm 1$$

does not change the number of independent continuous variables

$$\det R = 1$$

Right-handed frames only

SO(n): Special Orthogonal Group

- SO(n): Space of rotation matrices in $\mathbb{R}^n$

$$SO(n) = \{R \in \mathbb{R}^{n\times n} : RR^T = I, \det(R) = 1\}$$

- SO(3): space of 3D rotation matrices
- Group is a set G, with an operation ●, satisfying the following axioms:
  - Closure: $a \in G, b \in G \Rightarrow a \cdot b \in G$
  - Associativity: $(a \cdot b) \cdot c = a \cdot (b \cdot c), \forall a, b, c \in G$
  - Identity element: $\exists e \in G, e \cdot a = a, \forall a \in G$
  - Inverse element: $\forall a \in G, \exists b \in G, a \cdot b = b \cdot a = e$

Properties of Rotation Matrices

- Closure $R_1 R_2$
- Associativity $(R_1 R_2) R_3 = R_1 (R_2 R_3)$
- Identity element: identity matrix I
- Inverse element $R^{-1} = R^{\mathrm{T}}$
- Not commutative $R_1 R_2 \neq R_2 R_1$

Uses of Rotation Matrices

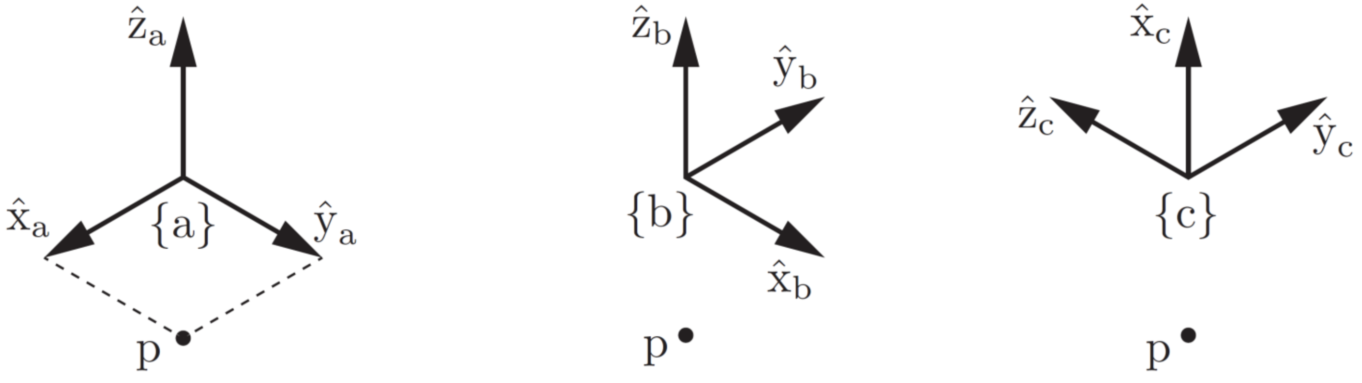
- Represent a rotation

- Change the reference frame

- Rotate a vector or a frame

Representing a Rotation

- R_{sc} frame {c} relative to frame {s}



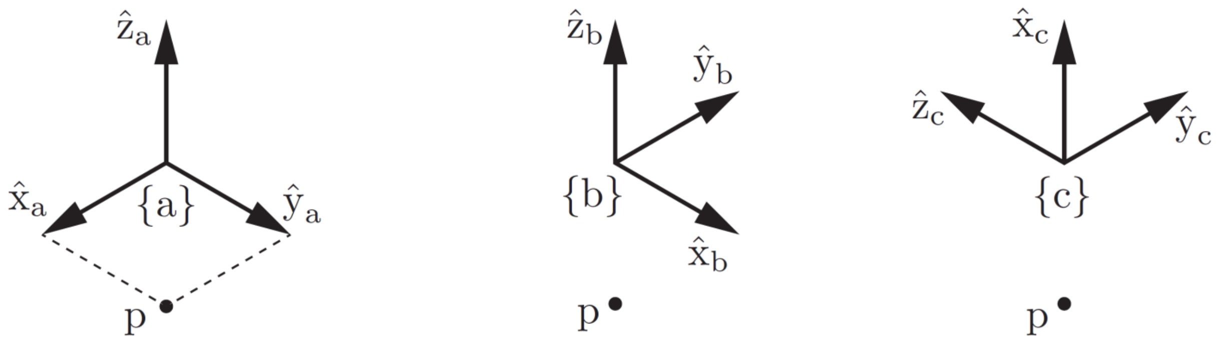
$$R_{ac} = \begin{bmatrix} 0 & -1 & 0 \\ 0 & 0 & -1 \\ 1 & 0 & 0 \end{bmatrix}$$

$$R_{ca} = \begin{bmatrix} 0 & 0 & 1 \\ -1 & 0 & 0 \\ 0 & -1 & 0 \end{bmatrix}$$

$$R_{ac}R_{ca} = I \qquad R_{ac} = R_{ca}^{-1} \qquad R_{ac} = R_{ca}^{\mathrm{T}}$$

Changing the Refence Frame

- Orientation of {b} in {a} R_{ab}
- Orientation of {c} in {b} R_{bc}
- Orientation of {c} in {a}



$$R_{ac} = R_{ab}R_{bc}$$

$$= \text{change\_reference\_frame\_from\_\{b\}\_to\_\{a\}}\,(R_{bc})$$

- Subscript cancel rule

$$R_{ab}R_{bc} = R_{a\cancel{b}}R_{\cancel{b}c} = R_{ac} \qquad R_{ab}p_b = R_{a\cancel{b}}p_{\cancel{b}} = p_a$$

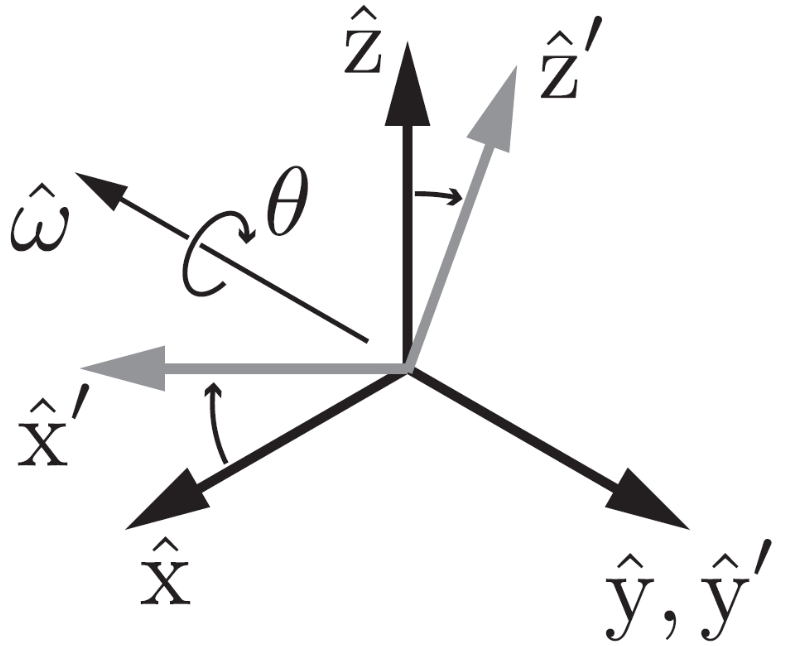
Rotating a Vector or a Frame

- Rotate frame {c} about a unit axis $\hat{\omega}$ by θ to get frame {c'}

$$R = R_{sc'}$$

- Rotation operation

$$R = \mathrm{Rot}(\hat{\omega}, \theta)$$



Rotating a Vector or a Frame

$$\mathrm{Rot}(\hat{\mathrm{x}}, \theta) = \begin{bmatrix} 1 & 0 & 0 \\ 0 & \cos\theta & -\sin\theta \\ 0 & \sin\theta & \cos\theta \end{bmatrix} \qquad \mathrm{Rot}(\hat{\mathrm{y}}, \theta) = \begin{bmatrix} \cos\theta & 0 & \sin\theta \\ 0 & 1 & 0 \\ -\sin\theta & 0 & \cos\theta \end{bmatrix}$$

$$\mathrm{Rot}(\hat{\mathrm{z}}, \theta) = \begin{bmatrix} \cos\theta & -\sin\theta & 0 \\ \sin\theta & \cos\theta & 0 \\ 0 & 0 & 1 \end{bmatrix}$$

Rotating a Vector or a Frame

$$\hat{\omega} = (\hat{\omega}_1, \hat{\omega}_2, \hat{\omega}_3)$$

$$\mathrm{Rot}(\hat{\omega}, \theta) =$$

$$\begin{bmatrix} c_\theta + \hat{\omega}_1^2(1 - c_\theta) & \hat{\omega}_1\hat{\omega}_2(1 - c_\theta) - \hat{\omega}_3 s_\theta & \hat{\omega}_1\hat{\omega}_3(1 - c_\theta) + \hat{\omega}_2 s_\theta \\ \hat{\omega}_1\hat{\omega}_2(1 - c_\theta) + \hat{\omega}_3 s_\theta & c_\theta + \hat{\omega}_2^2(1 - c_\theta) & \hat{\omega}_2\hat{\omega}_3(1 - c_\theta) - \hat{\omega}_1 s_\theta \\ \hat{\omega}_1\hat{\omega}_3(1 - c_\theta) - \hat{\omega}_2 s_\theta & \hat{\omega}_2\hat{\omega}_3(1 - c_\theta) + \hat{\omega}_1 s_\theta & c_\theta + \hat{\omega}_3^2(1 - c_\theta) \end{bmatrix}$$

$$s_\theta = \sin\theta \qquad c_\theta = \cos\theta$$

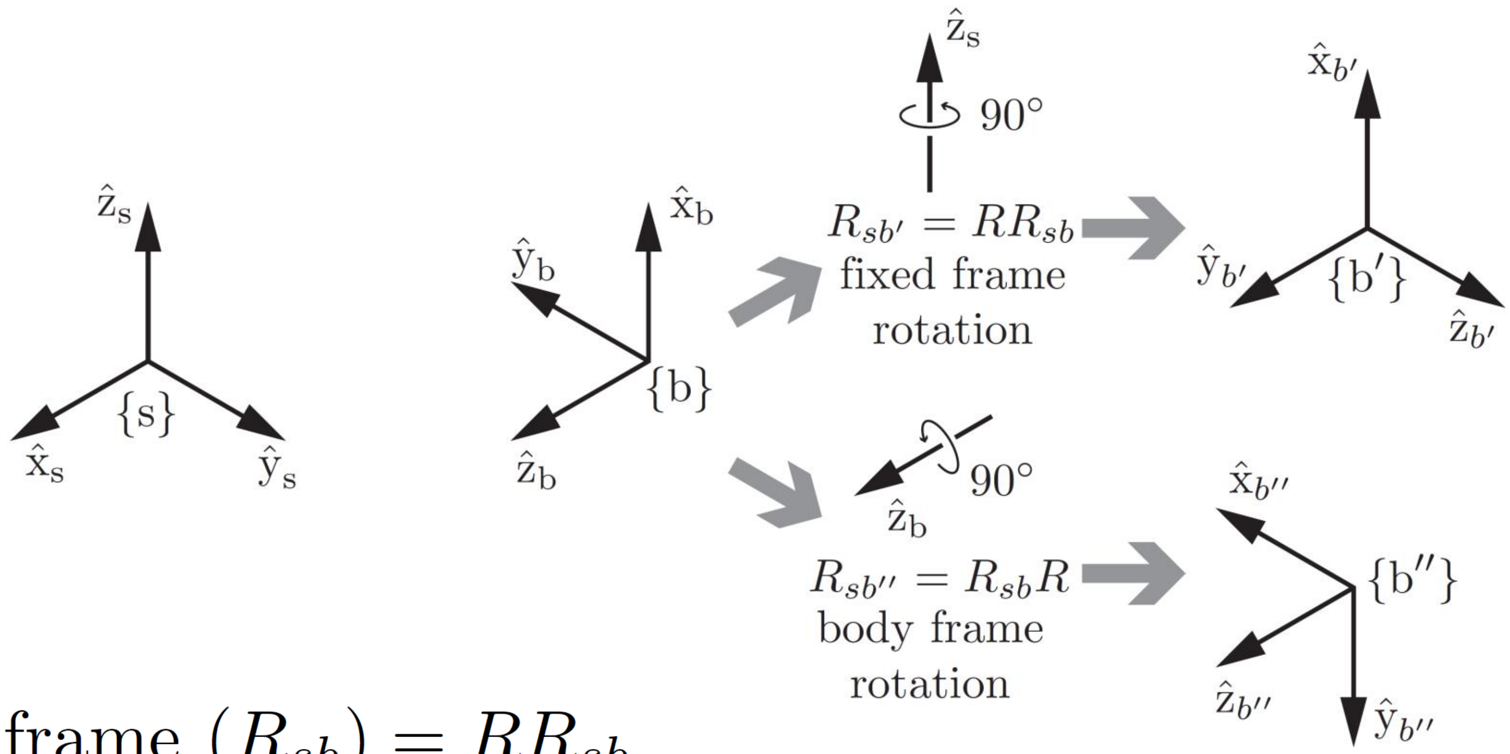
$$\mathrm{Rot}(\hat{\omega}, \theta) = \mathrm{Rot}(-\hat{\omega}, -\theta)$$

Rotating a Vector or a Frame

- {b} in {s} R_{sb}
- Rotate {b} with

$$\mathrm{Rot}(\hat{\omega}, \theta)$$

$\hat{\omega}$ represented in {s} or {b}?



$$R_{sb'} = \text{rotate\_by\_}R\text{\_in\_\{s\}\_frame }(R_{sb}) = RR_{sb}$$

$$R_{sb''} = \text{rotate\_by\_}R\text{\_in\_\{b\}\_frame }(R_{sb}) = R_{sb}R$$

To rotate a vector $v' = Rv$

Summary

- Reference frames
- Rigid-body motions in 2D
- Rigid-body motions in 3D
  - Rotation matrices
- Uses of Rotation Matrices
  - Represent a rotation
  - Change the reference frame
  - Rotate a vector or a frame

Further Reading

- Chapter 3 in Kevin M. Lynch and Frank C. Park. Modern Robotics: Mechanics, Planning, and Control. 1st Edition, 2017

- Quaternion and Rotations, Yan-Bin Jia, https://graphics.stanford.edu/courses/cs348a-17-winter/Papers/quaternion.pdf

- Introduction to Robotics, Prof. Wei Zhang, OSU, Lecture 3, Rotational Motion, http://www2.ece.ohio-state.edu/~zhang/RoboticsClass/index.html