Inverse Kinematics

CS 6301 Special Topics: Introduction to Robot Manipulation and Navigation

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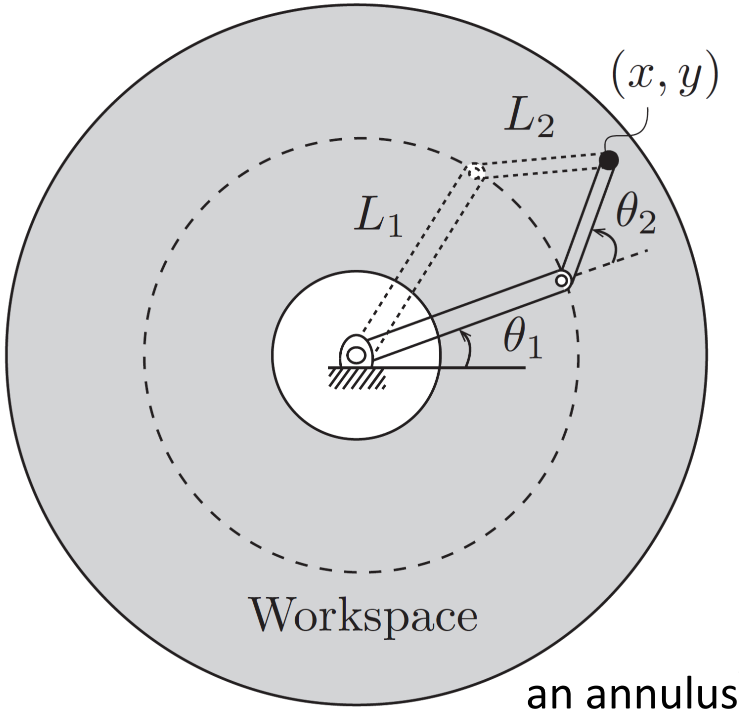
Inverse Kinematics

- For a n degree-of-freedom open chain with forward kinematics
  $T(\theta) \quad \theta \in \mathbb{R}^n$

- Given a homogenous transformation $X \in SE(3)$

- Find solutions θ such that $T(\theta) = X$

Inverse Kinematics



an annulus

Two-link planar open chain

Forward kinematics

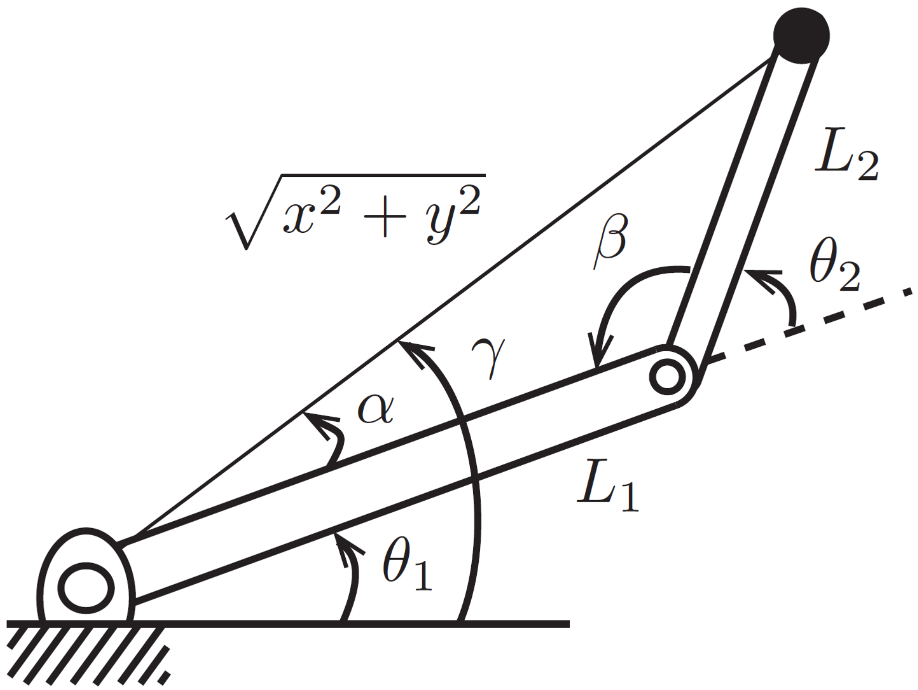
$$\begin{bmatrix} x \\ y \end{bmatrix} = \begin{bmatrix} L_1 \cos\theta_1 + L_2 \cos(\theta_1 + \theta_2) \\ L_1 \sin\theta_1 + L_2 \sin(\theta_1 + \theta_2) \end{bmatrix}$$

Assuming $L_1 > L_2$

Give (x, y)

There can be zero, one, or two solutions for (θ_1, θ_2)

Inverse Kinematics



Two-link planar open chain

Law of cosines $c^2 = a^2 + b^2 - 2ab\cos C$

$$L_1^2 + L_2^2 - 2L_1L_2\cos\beta = x^2 + y^2$$

$$\beta = \cos^{-1}\left(\frac{L_1^2 + L_2^2 - x^2 - y^2}{2L_1L_2}\right)$$

$$\alpha = \cos^{-1}\left(\frac{x^2 + y^2 + L_1^2 - L_2^2}{2L_1\sqrt{x^2+y^2}}\right)$$

$$\gamma = \operatorname{atan2}(y, x) \quad (-\pi, \pi]$$

righty solution $\theta_1 = \gamma - \alpha, \quad \theta_2 = \pi - \beta$

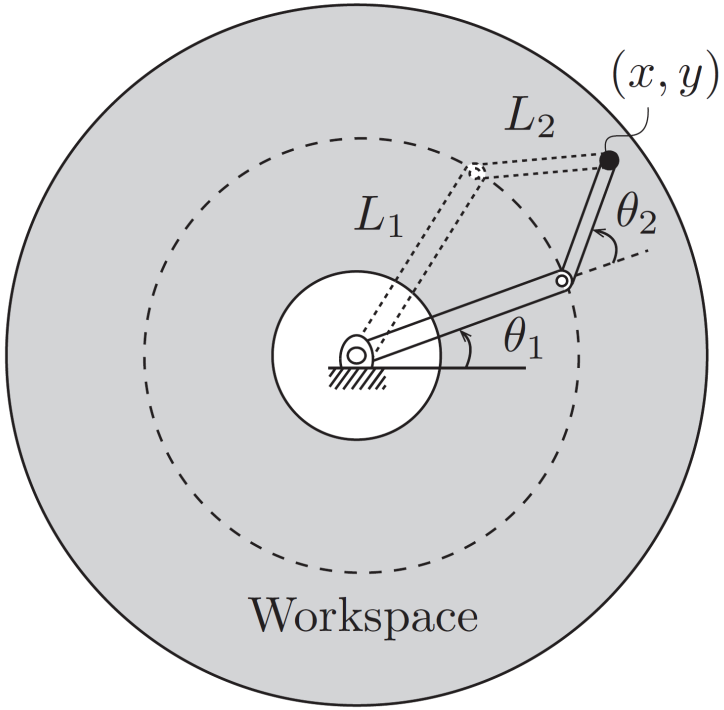
lefty solution $\theta_1 = \gamma + \alpha, \quad \theta_2 = \beta - \pi$

Inverse Kinematics

- IK can have multiple solutions
- FK only has a single solution
- Find solutions θ such that

$$T(\theta) = X$$

- Finding the roots of a nonlinear equation



Analytic Inverse Kinematics

Newton-Raphson Method

- Solve $g(\theta) = 0$ $\quad g : \mathbb{R} \rightarrow \mathbb{R}$ differentiable
- Initial guess θ^0
- Taylor expansion

$$g(\theta) = g(\theta^0) + \frac{\partial g}{\partial \theta}(\theta^0)(\theta - \theta^0) + \text{higher-order terms (h.o.t)}$$

$$\text{set } g(\theta) = 0 \qquad \theta = \theta^0 - \left(\frac{\partial g}{\partial \theta}(\theta^0)\right)^{-1} g(\theta^0)$$

$$\theta^{k+1} = \theta^k - \left(\frac{\partial g}{\partial \theta}(\theta^k)\right)^{-1} g(\theta^k)$$

Newton-Raphson Method

- When g is multi-dimensional $g : \mathbb{R}^n \rightarrow \mathbb{R}^n$

$$\frac{\partial g}{\partial \theta}(\theta) = \begin{bmatrix} \frac{\partial g_1}{\partial \theta_1}(\theta) & \cdots & \frac{\partial g_1}{\partial \theta_n}(\theta) \\ \vdots & \ddots & \vdots \\ \frac{\partial g_n}{\partial \theta_1}(\theta) & \cdots & \frac{\partial g_n}{\partial \theta_n}(\theta) \end{bmatrix} \in \mathbb{R}^{n \times n}$$

Numerical Inverse Kinematics Algorithm

- Forward kinematics $x = f(\theta)$ $f : \mathbb{R}^n \rightarrow \mathbb{R}^m$
- Desired end-effector coordinates x_d
- Objective function for the Newton-Raphson method

$$g(\theta) = x_d - f(\theta)$$

- Goal

$$g(\theta_d) = x_d - f(\theta_d) = 0$$

- Initial guess θ^0

Numerical Inverse Kinematics Algorithm

- Taylor expansion

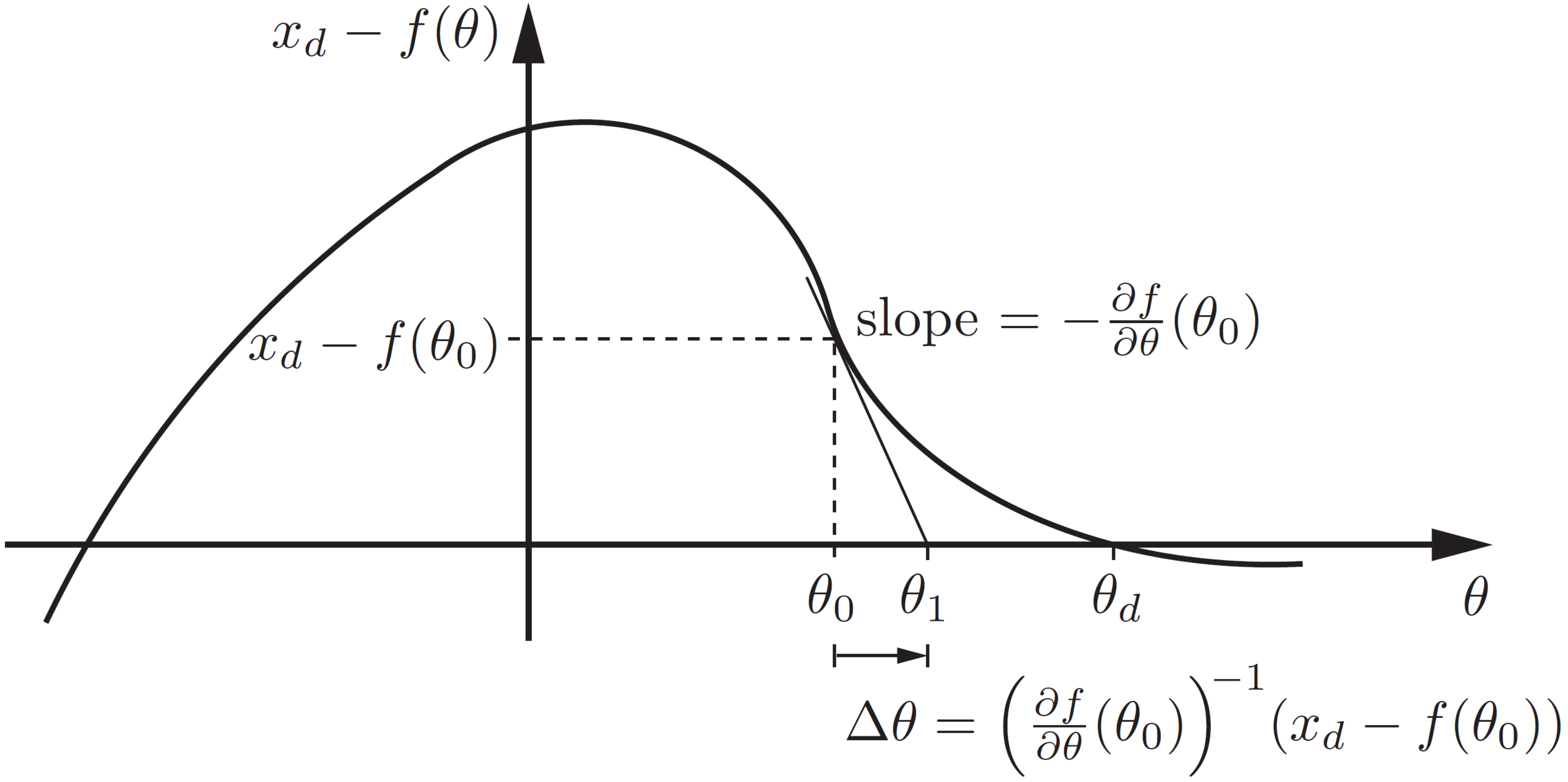
$$x_d = f(\theta_d) = f(\theta^0) + \underbrace{\left.\frac{\partial f}{\partial \theta}\right|_{\theta^0}}_{J(\theta^0)} \underbrace{(\theta_d - \theta^0)}_{\Delta\theta} + \text{h.o.t.},$$

$J(\theta^0) \in \mathbb{R}^{m \times n}$ Jacobian

$$J(\theta^0)\Delta\theta = x_d - f(\theta^0)$$

Whe $J(\theta^0)$ is square and invertible $\Delta\theta = J^{-1}(\theta^0)\left(x_d - f(\theta^0)\right)$

Numerical Inverse Kinematics Algorithm



Numerical Inverse Kinematics Algorithm

- When J is not invertible, use pseudoinverse $J^\dagger$

$$Jy = z \qquad J \in \mathbb{R}^{m \times n},\ y \in \mathbb{R}^n,\ \text{and}\ z \in \mathbb{R}^m$$

$$y^* = J^\dagger z$$

$$J^\dagger = J^{\mathrm{T}}(JJ^{\mathrm{T}})^{-1} \qquad \text{if } J \text{ is fat, } n > m \text{ (called a right inverse since } JJ^\dagger = I)$$
$$J^\dagger = (J^{\mathrm{T}}J)^{-1}J^{\mathrm{T}} \qquad \text{if } J \text{ is tall, } n < m \text{ (called a left inverse since } J^\dagger J = I).$$

$$\Delta\theta = J^\dagger(\theta^0)\left(x_d - f(\theta^0)\right)$$

Numerical Inverse Kinematics Algorithm

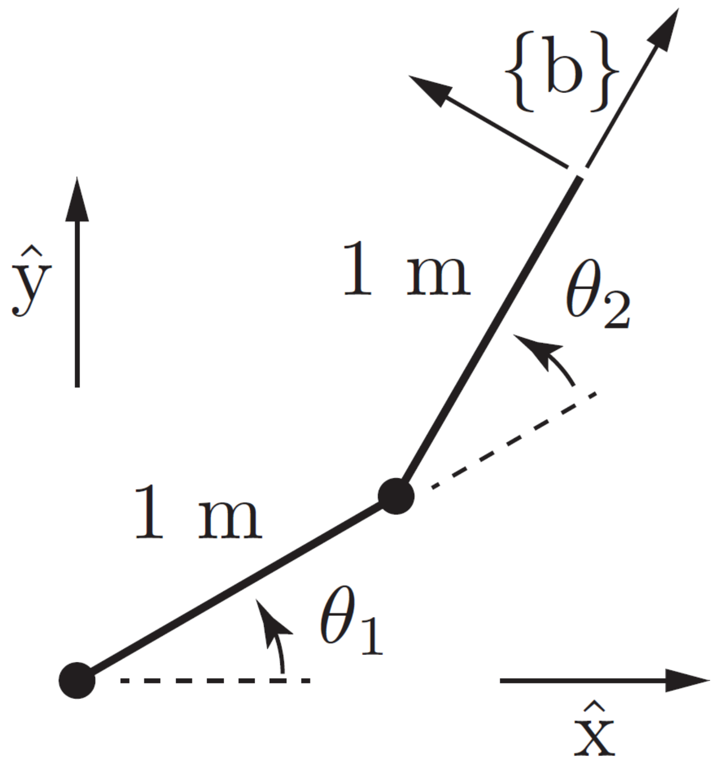
- How to achieve a desired end-effector configuration $T_{sd} \in SE(3)$

- Current configuration $T_{sb}(\theta^i)$
- Desired configuration $T_{bd}(\theta^i) = T_{sb}^{-1}(\theta^i)T_{sd} = T_{bs}(\theta^i)T_{sd}$
- Body twist $[\mathcal{V}_b] = \log T_{bd}(\theta^i)$

- Updating rule

$$\theta^{i+1} = \theta^i + J_b^{\dagger}(\theta^i)\mathcal{V}_b$$

Numerical Inverse Kinematics

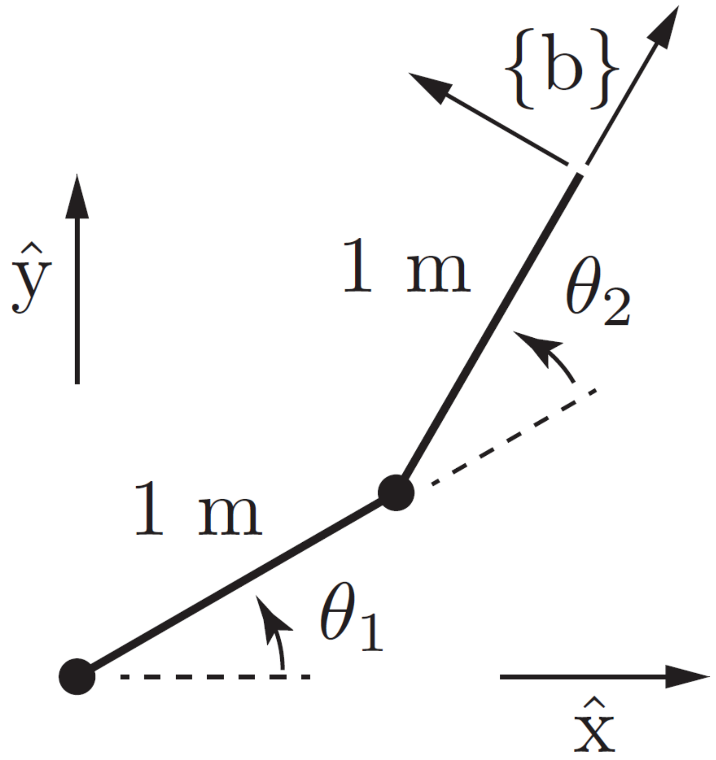


A 2R robot

$$(x, y) = (0.366 \text{ m}, 1.366 \text{ m})$$
$$\theta_d = (30°, 90°)$$

$$T_{sd} = \begin{bmatrix} -0.5 & -0.866 & 0 & 0.366 \\ 0.866 & -0.5 & 0 & 1.366 \\ 0 & 0 & 1 & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix}$$

Numerical Inverse Kinematics



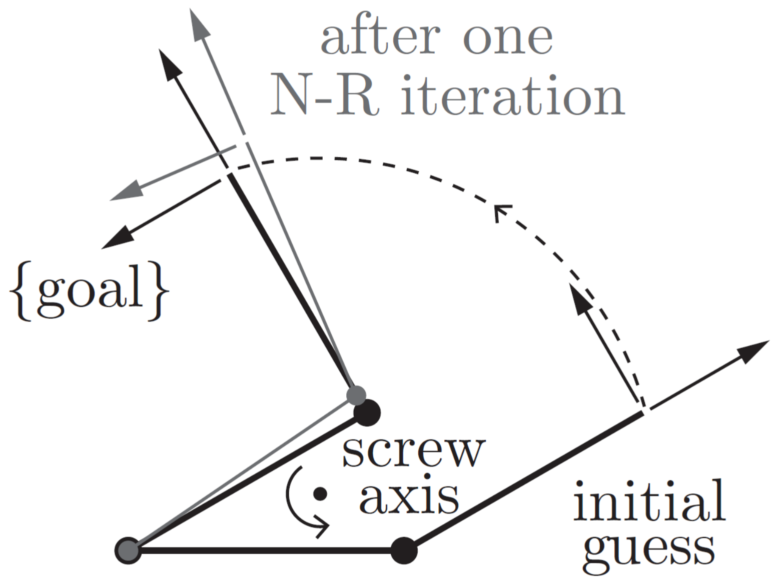
- Forward kinematics

$$M = \begin{bmatrix} 1 & 0 & 0 & 2 \\ 0 & 1 & 0 & 0 \\ 0 & 0 & 1 & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix} \quad \mathcal{B}_1 = \begin{bmatrix} 0 \\ 0 \\ 1 \\ 0 \\ 2 \\ 0 \end{bmatrix} \quad \mathcal{B}_2 = \begin{bmatrix} 0 \\ 0 \\ 1 \\ 0 \\ 1 \\ 0 \end{bmatrix}$$

- Initial guess $\theta^0 = (0, 30^\circ)$

Numerical Inverse Kinematics

$$(\omega_{zb}, v_{xb}, v_{yb})$$



i	$(\theta_1,\ \theta_2)$	(x, y)	$\mathcal{V}_b = (\omega_{zb}, v_{xb}, v_{yb})$	$\lVert\omega_b\rVert$	$\lVert v_b\rVert$
0	$(0.00, 30.00^\circ)$	$(1.866, 0.500)$	$(1.571, 0.498, 1.858)$	1.571	1.924
1	$(34.23^\circ, 79.18^\circ)$	$(0.429, 1.480)$	$(0.115, -0.074, 0.108)$	0.115	0.131
2	$(29.98^\circ, 90.22^\circ)$	$(0.363, 1.364)$	$(-0.004, 0.000, -0.004)$	0.004	0.004
3	$(30.00^\circ, 90.00^\circ)$	$(0.366, 1.366)$	$(0.000, 0.000, 0.000)$	0.000	0.000

Inverse Velocity Kinematics

- Find the joint velocity $\dot{\theta}$ to follow a desired end-effector trajectory $T_{sd}(t)$
- Method 1: uses inverse kinematics to compute $\theta_d(k\Delta t)$

Joint velocity $\dot{\theta} = \big(\theta_d(k\Delta t) - \theta((k-1)\Delta t)\big)/\Delta t$

interval $[(k-1)\Delta t, k\Delta t]$

- Method 2: uses $J\dot{\theta} = \mathcal{V}_d$

$$\dot{\theta} = J^{\dagger}(\theta)\mathcal{V}_d$$

Body twist $T_{sd}^{-1}(t)\dot{T}_{sd}(t)$ Spatial twist $\dot{T}_{sd}(t)T_{sd}^{-1}(t)$

Summary

- Inverse kinematics
- Newton-Raphson Method
- Numerical Inverse Kinematics Algorithm

Further Reading

- Chapter 6 and Appendix D in Kevin M. Lynch and Frank C. Park. Modern Robotics: Mechanics, Planning, and Control. 1st Edition, 2017.