Dynamics of Open Chains

CS 6341 Robotics

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Robot Dynamics

- Dynamic equations (equations of motion)

$$M(\theta) \in \mathbb{R}^{n \times n}$$

Mass matrix

$$h(\theta, \dot{\theta}) \in \mathbb{R}^{n}$$

Centripetal, Coriolis, gravity, friction

$$\tau = M(\theta)\ddot{\theta} + h(\theta, \dot{\theta})$$

$$\tau \in \mathbb{R}^{n}$$

Joint forces and torques

$$\theta \in \mathbb{R}^{n}$$

Joint variables

This equation can be very complex

Robot Dynamics

- Forward dynamics
  - Given robot state $(\theta, \dot{\theta})$ and the joint forces and torques τ
  - Determine the robot's acceleration $\ddot{\theta}$

$$\ddot{\theta} = M^{-1}(\theta)\big(\tau - h(\theta, \dot{\theta})\big)$$

Simulation

- Inverse dynamics
  - Given robot state $(\theta, \dot{\theta})$ and a desired acceleration $\ddot{\theta}$ (from motion planning)
  - Find the joint forces and torques τ

$$\tau = M(\theta)\ddot{\theta} + h(\theta, \dot{\theta})$$

Control

Robot Dynamics

- How to find this equation for a robot manipulator?

$$\tau = M(\theta)\ddot{\theta} + h(\theta, \dot{\theta})$$

Last Lecture: Dynamics of a Single Rigid Body

- Body twist $\mathcal{V}_b = (\omega_b, v_b)$

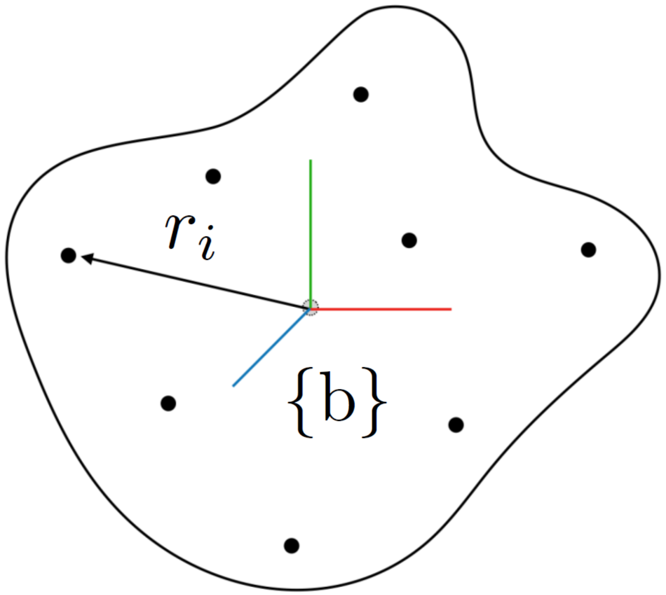
- Linear dynamics

$$f_b = \mathfrak{m}(\dot{v}_b + [\omega_b]v_b)$$

- Rotational dynamics

$$m_b = \mathcal{I}_b\dot{\omega}_b + [\omega_b]\mathcal{I}_b\omega_b$$

$$\mathcal{I}_b = -\sum_i \mathfrak{m}_i[r_i]^2 \in \mathbb{R}^{3\times 3}$$



Twist-Wrench Formulation

- Linear dynamics $f_b = \mathfrak{m}(\dot{v}_b + [\omega_b]v_b)$
- Rotation dynamics $m_b = \mathcal{I}_b\dot{\omega}_b + [\omega_b]\mathcal{I}_b\omega_b$

$$\begin{bmatrix} m_b \\ f_b \end{bmatrix} = \begin{bmatrix} \mathcal{I}_b & 0 \\ 0 & \mathfrak{m}I \end{bmatrix} \begin{bmatrix} \dot{\omega}_b \\ \dot{v}_b \end{bmatrix} + \begin{bmatrix} [\omega_b] & 0 \\ 0 & [\omega_b] \end{bmatrix} \begin{bmatrix} \mathcal{I}_b & 0 \\ 0 & \mathfrak{m}I \end{bmatrix} \begin{bmatrix} \omega_b \\ v_b \end{bmatrix}$$

Body wrench

$$\mathcal{F}_b = \begin{bmatrix} m_b \\ f_b \end{bmatrix}$$

Spatial inertia matrix

$$\mathcal{G}_b = \begin{bmatrix} \mathcal{I}_b & 0 \\ 0 & \mathfrak{m}I \end{bmatrix}$$

$$\mathcal{G}_b \in \mathbb{R}^{6\times 6}$$

Spatial momentum

$$\mathcal{P}_b = \begin{bmatrix} \mathcal{I}_b\omega_b \\ \mathfrak{m}v_b \end{bmatrix} = \begin{bmatrix} \mathcal{I}_b & 0 \\ 0 & \mathfrak{m}I \end{bmatrix} \begin{bmatrix} \omega_b \\ v_b \end{bmatrix} = \mathcal{G}_b\mathcal{V}_b$$

$$\mathcal{P}_b \in \mathbb{R}^6$$

Body twist

$$\mathcal{V}_b = \begin{bmatrix} \omega_b \\ v_b \end{bmatrix}$$

Twist-Wrench Formulation

$$\mathcal{F}_b = \mathcal{G}_b \dot{\mathcal{V}}_b - \begin{bmatrix} [\omega_b] & 0 \\ 0 & [\omega_b] \end{bmatrix} \mathcal{G}_b \mathcal{V}_b$$

We can show that (see Lynch & Park 8.2.2)

$$\begin{aligned} \mathcal{F}_b &= \mathcal{G}_b \dot{\mathcal{V}}_b - \mathrm{ad}^{\mathrm{T}}_{\mathcal{V}_b}(\mathcal{P}_b) \\ &= \mathcal{G}_b \dot{\mathcal{V}}_b - [\mathrm{ad}_{\mathcal{V}_b}]^{\mathrm{T}} \mathcal{G}_b \mathcal{V}_b \end{aligned}$$

Lie bracket of twist

$$[\mathrm{ad}_{\mathcal{V}_b}] = \begin{bmatrix} [\omega_b] & 0 \\ [v_b] & [\omega_b] \end{bmatrix}$$

$$\tau = M(\theta)\ddot{\theta} + h(\theta, \dot{\theta})$$

Dynamics of a Single Rigid Body

- Inverse dynamics

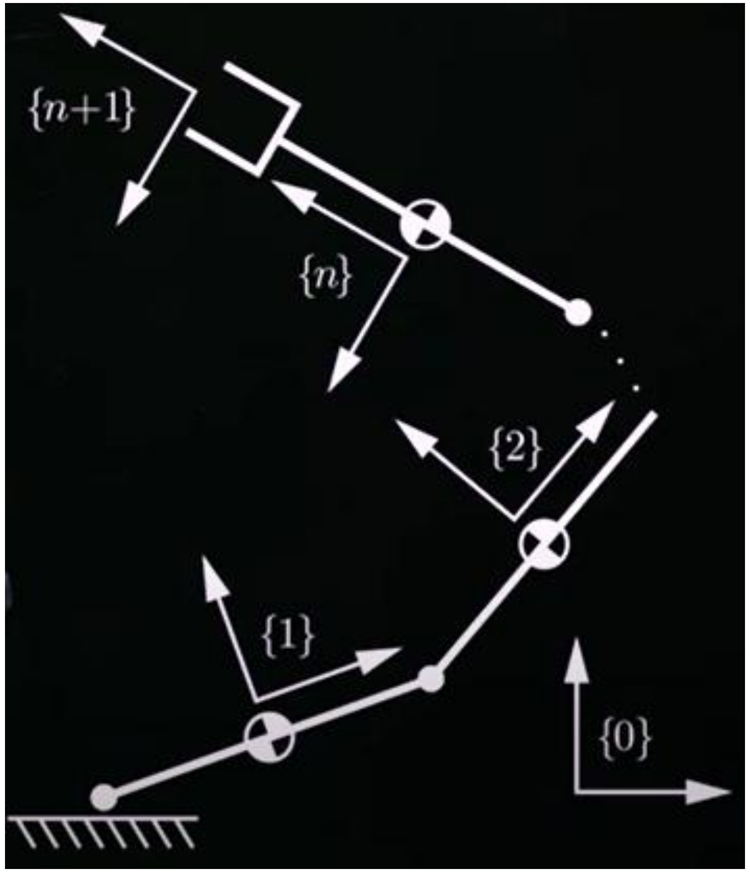
$$\mathcal{F}_b \;=\; \mathcal{G}_b\dot{\mathcal{V}}_b - [\mathrm{ad}_{\mathcal{V}_b}]^{\mathrm{T}}\mathcal{G}_b\mathcal{V}_b$$

- Forward dynamics

$$\dot{\mathcal{V}}_b = \mathcal{G}_b^{-1}(\mathcal{F}_b + [\mathrm{ad}_{\mathcal{V}_b}]^{\mathrm{T}}\mathcal{G}_b\mathcal{V}_b)$$

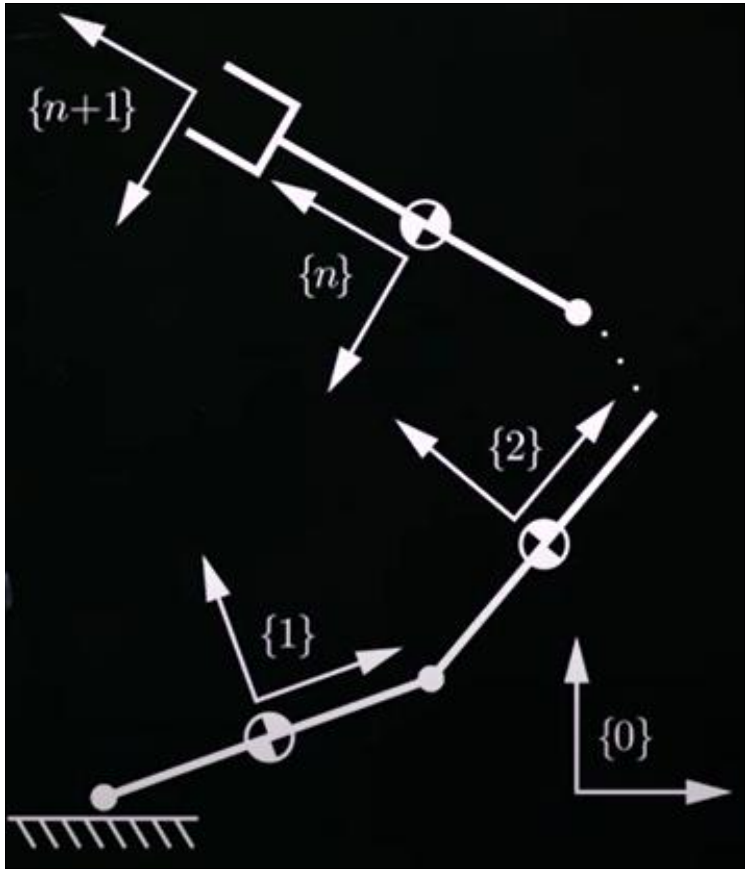
Inverse Dynamics of Open Chains

- N-link open chain
- A body-fixed reference frame {i} is attached to the center of mass of each link i
- Base frame {0}, end-effector frame {n+1} (fixed in {n})



Inverse Dynamics of Open Chains

- At home position (all joints are zeros)
  - Configuration of frame {j} in {i} $M_{i,j} \in SE(3)$
  - Configuration of {i} in base frame {0} $M_i = M_{0,i}$



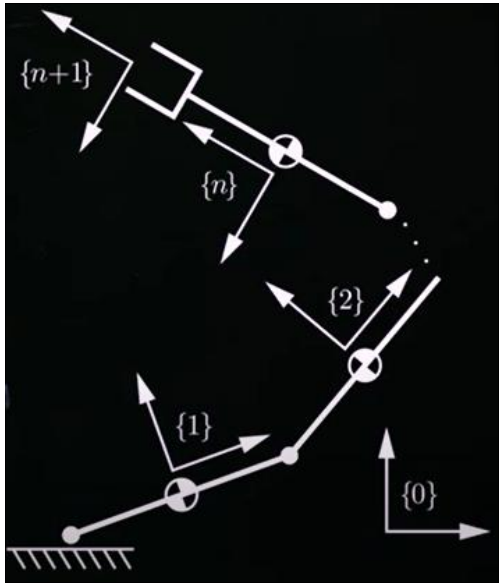
$$M_{i-1,i} = M_{i-1}^{-1} M_i$$

$$M_{i,i-1} = M_i^{-1} M_{i-1}$$

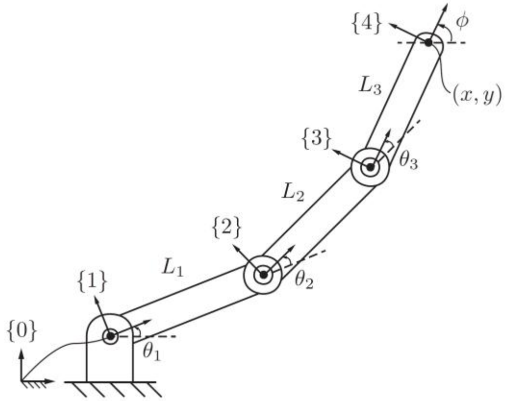
Inverse Dynamics of Open Chains

- Screw axis for joint i in link frame {i} $\mathcal{A}_i$, in space frame {0} $\mathcal{S}_i$

$$\mathcal{A}_i = \mathrm{Ad}_{M_i^{-1}}(\mathcal{S}_i)$$



- Recall screw axis

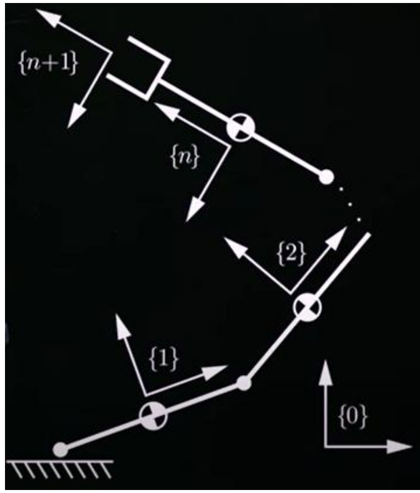


$$\mathcal{S}_3 = \begin{bmatrix} \omega_3 \\ v_3 \end{bmatrix} = \begin{bmatrix} 0 \\ 0 \\ 1 \\ 0 \\ -(L_1 + L_2) \\ 0 \end{bmatrix}$$

$$\mathcal{S}_a = [\mathrm{Ad}_{T_{ab}}]\mathcal{S}_b \qquad [\mathrm{Ad}_T] = \begin{bmatrix} R & 0 \\ [p]R & R \end{bmatrix} \in \mathbb{R}^{6\times 6}$$

Inverse Dynamics of Open Chains

- Screw axis for joint i in link frame {i} $\mathcal{A}_i$, in space frame {0} $\mathcal{S}_i$



- The configuration of {j} in {i} with joint variables $T_{i,j} \in SE(3)$

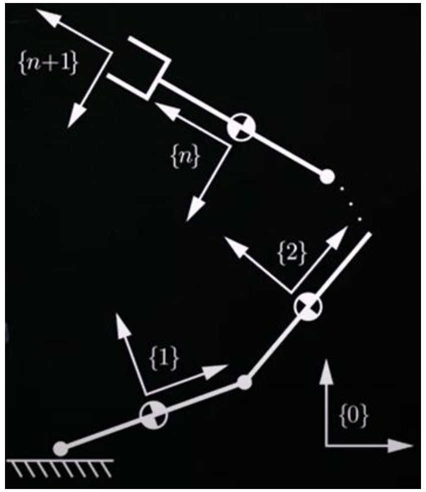
$$T_{i-1,i}(\theta_i) \qquad T_{i,i-1}(\theta_i) = T^{-1}_{i-1,i}(\theta_i)$$

$$T_{i-1,i}(\theta_i) = M_{i-1,i}e^{[\mathcal{A}_i]\theta_i} \quad T_{i,i-1}(\theta_i) = e^{-[\mathcal{A}_i]\theta_i}M_{i,i-1}$$

- Twist of link frame {i} expressed in {i} $\mathcal{V}_i = (\omega_i, v_i)$
- Wrench transmitted through joint i to link frame {i} expressed in {i}

$$\mathcal{F}_i = (m_i, f_i)$$

Inverse Dynamics of Open Chains



- Spatial inertia matrix of link i $\mathcal{G}_i \in \mathbb{R}^{6\times 6}$ $\mathcal{G}_i = \begin{bmatrix} \mathcal{I}_i & 0 \\ 0 & \mathfrak{m}_i I \end{bmatrix}$

- Recursively calculate the twist and acceleration, moving from the base to the tip

$$\mathcal{V}_i = \mathcal{A}_i\dot{\theta}_i + [\mathrm{Ad}_{T_{i,i-1}}]\mathcal{V}_{i-1}$$

(Velocity for link i)

Twist from joint i

Twist from previous link i-1

$$\dot{\mathcal{V}}_i = \mathcal{A}_i\ddot{\theta}_i + [\mathrm{Ad}_{T_{i,i-1}}]\dot{\mathcal{V}}_{i-1} + \frac{d}{dt}\left([\mathrm{Ad}_{T_{i,i-1}}]\right)\mathcal{V}_{i-1}$$

See Lynch & Park for derivation

$$\dot{\mathcal{V}}_i = \mathcal{A}_i\ddot{\theta}_i + [\mathrm{Ad}_{T_{i,i-1}}]\dot{\mathcal{V}}_{i-1} + [\mathrm{ad}_{\mathcal{V}_i}]\mathcal{A}_i\dot{\theta}_i$$

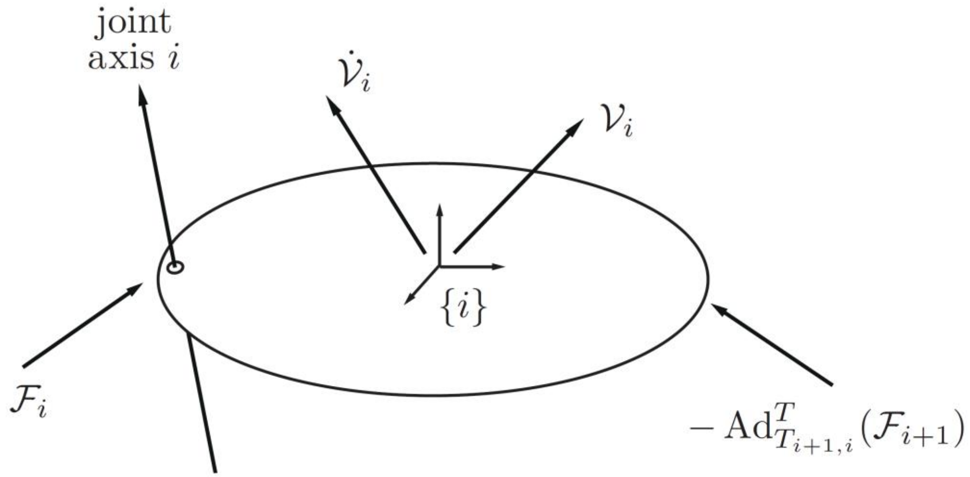
$$[\mathrm{ad}_{\mathcal{V}}] = \begin{bmatrix} [\omega] & 0 \\ [v] & [\omega] \end{bmatrix} \in \mathbb{R}^{6\times 6}$$

Inverse Dynamics of Open Chains

$$\mathcal{F}_b = [\mathrm{Ad}_{T_{ab}}]^{\mathrm{T}} \mathcal{F}_a$$

- Accelerations from base to tip

$$\dot{\mathcal{V}}_i = \mathcal{A}_i \ddot{\theta}_i + [\mathrm{Ad}_{T_{i,i-1}}]\dot{\mathcal{V}}_{i-1} + [\mathrm{ad}_{\mathcal{V}_i}]\mathcal{A}_i \dot{\theta}_i$$



- Recall rigid body dynamic equations

$$\begin{aligned} \mathcal{F}_b &= \mathcal{G}_b \dot{\mathcal{V}}_b - \mathrm{ad}^{\mathrm{T}}_{\mathcal{V}_b}(\mathcal{P}_b) \\ &= \mathcal{G}_b \dot{\mathcal{V}}_b - [\mathrm{ad}_{\mathcal{V}_b}]^{\mathrm{T}} \mathcal{G}_b \mathcal{V}_b \end{aligned}$$

- Wrench on link i from joint i and joint i+1

$$\mathcal{G}_i \dot{\mathcal{V}}_i - \mathrm{ad}^{\mathrm{T}}_{\mathcal{V}_i}(\mathcal{G}_i \mathcal{V}_i) = \mathcal{F}_i - \mathrm{Ad}^{\mathrm{T}}_{T_{i+1,i}}(\mathcal{F}_{i+1})$$

Inverse Dynamics

- Solve the wrench from tip to base $\mathcal{F}_i$

- Force or torque at the joint in the direction of the joint's screw axis

$$\tau_i \dot{\theta}_i = \mathcal{F}_i^{\mathrm{T}} \mathcal{A}_i \dot{\theta}_i$$

Principle of conservation of power

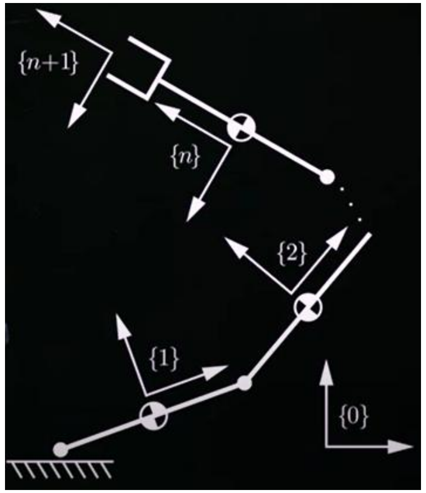
Power = force × velocity

$$\tau_i = \mathcal{F}_i^{\mathrm{T}} \mathcal{A}_i$$

- Newton-Euler Inverse Dynamics Algorithm

Newton-Euler Inverse Dynamics Algorithm

Given $\theta, \dot{\theta}, \ddot{\theta}$ Compute τ



Forward iterations Given $\theta, \dot{\theta}, \ddot{\theta}$, for $i = 1$ to n do

$$\mathcal{V}_0 = (0, 0)$$

$$\dot{\mathcal{V}}_0 = (0, -g)$$

$$\begin{aligned} T_{i,i-1} &= e^{-[\mathcal{A}_i]\theta_i} M_{i,i-1}, \\ \mathcal{V}_i &= \mathrm{Ad}_{T_{i,i-1}}(\mathcal{V}_{i-1}) + \mathcal{A}_i \dot{\theta}_i, \\ \dot{\mathcal{V}}_i &= \mathrm{Ad}_{T_{i,i-1}}(\dot{\mathcal{V}}_{i-1}) + \mathrm{ad}_{\mathcal{V}_i}(\mathcal{A}_i)\dot{\theta}_i + \mathcal{A}_i \ddot{\theta}_i. \end{aligned}$$

Backward iterations For $i = n$ to 1 do

$$\mathcal{F}_{n+1} = \mathcal{F}_{\text{tip}} = (m_{\text{tip}}, f_{\text{tip}})$$

The wrench applied to the environment by the end-effector

$$\begin{aligned} \mathcal{F}_i &= \mathrm{Ad}^{\mathrm{T}}_{T_{i+1,i}}(\mathcal{F}_{i+1}) + \mathcal{G}_i \dot{\mathcal{V}}_i - \mathrm{ad}^{\mathrm{T}}_{\mathcal{V}_i}(\mathcal{G}_i \mathcal{V}_i), \\ \tau_i &= \mathcal{F}_i^{\mathrm{T}} \mathcal{A}_i. \end{aligned}$$

Statics of Open Chains

- Principle of conservation of power

power at the joints = (power to move the robot) + (power at the end-effector)

- Considering the robot to be at static equilibrium (no power to move robot)

$$\tau^{\mathrm{T}}\dot{\theta} = \mathcal{F}_b^{\mathrm{T}}\mathcal{V}_b$$

power at the end-effector

$$\mathcal{V}_b = J_b(\theta)\dot{\theta}$$

$$\tau = J_b^{\mathrm{T}}(\theta)\mathcal{F}_b$$

Statics of Open Chains

- If an external wrench $-\mathcal{F}$ is applied to the end-effector when the robot is at equilibrium, joint torque to keep the robot at equilibrium

$$\tau = J^{\mathrm{T}}(\theta)\mathcal{F}$$

- Equations of motion with external wrench on the end-effector

$$\tau - J^T(\theta)\mathcal{F}_{\mathrm{tip}} = M(\theta)\ddot{\theta} + h(\theta, \dot{\theta})$$

Forward Dynamics of Open Chains

- Forward dynamics $M(\theta)\ddot{\theta} = \tau(t) - h(\theta, \dot{\theta}) - J^{\mathrm{T}}(\theta)\mathcal{F}_{\mathrm{tip}}$
  - Given $\theta, \ \dot{\theta}, \ \tau \ \mathcal{F}_{\mathrm{tip}}$ Solve $\ddot{\theta}$

- $h(\theta, \dot{\theta})$ can be computed by the inverse dynamics algorithm with $\ddot{\theta} = 0$ and $\mathcal{F}_{\mathrm{tip}} = 0$

- We can solve

$$M\ddot{\theta} = b, \text{ for } \ddot{\theta}$$

$$b = \tau(t) - h(\theta, \dot{\theta}) - J^{\mathrm{T}}(\theta)\mathcal{F}_{\mathrm{tip}}$$

Forward Dynamics of Open Chains

- Simulate the motion of a robot

$$\ddot{\theta} = ForwardDynamics(\theta, \dot{\theta}, \tau, \mathcal{F}_{\text{tip}})$$

First-order differential equations

$$q_1 = \theta, \; q_2 = \dot{\theta}$$

$$\begin{aligned} \dot{q}_1 &= q_2, \\ \dot{q}_2 &= ForwardDynamics(q_1, q_2, \tau, \mathcal{F}_{\text{tip}}) \end{aligned}$$

First-order Euler iteration

$$\begin{aligned} q_1(t+\delta t) &= q_1(t) + q_2(t)\delta t, \\ q_2(t+\delta t) &= q_2(t) + ForwardDynamics(q_1, q_2, \tau, \mathcal{F}_{\text{tip}})\delta t \end{aligned}$$

Initial values $q_1(0) = \theta(0)$ and $q_2(0) = \dot{\theta}(0)$

Summary

- Robot Dynamics
- Newton-Euler Inverse Dynamics Algorithm
- Forward Dynamics of Open Chains

Further Reading

- Sections 3.4, 4.3 and Chapter 8 in Kevin M. Lynch and Frank C. Park. Modern Robotics: Mechanics, Planning, and Control. 1st Edition, 2017.