

# Contents

<b>1</b>	<b>Introduction</b>	<b>1</b>
1.1	Mobile Robotics	2
1.1.1	Autonomous Robots	3
1.1.2	Other Classifications of Mobile Robots	5
1.2	Vehicle-Manipulator Systems	5
1.2.1	Definition	6
1.2.2	Classifications of Vehicle-Manipulator Systems	6
1.2.3	Challenges of Implementing Vehicle-Manipulator Systems	9
1.2.4	The Importance of Robust Solutions	11
1.2.5	A Larger Perspective	12
	References	12
<b>2</b>	<b>Preliminary Mathematical Concepts</b>	<b>15</b>
2.1	Reference Frames	17
2.1.1	Inertial Reference Frames	17
2.1.2	Non-inertial Reference Frames	18
2.2	Coordinate Systems	19
2.2.1	Cartesian Basis	20
2.3	Euclidean and Non-Euclidean Transformations	22
2.4	Quasi-coordinates and Quasi-velocities	25
2.5	Topological Spaces and Manifolds	27
2.5.1	Coordinate Charts	31
2.5.2	Manifolds Again	35
2.6	Lie Groups	36
2.6.1	Some Important Lie Groups	38
2.6.2	Matrix Lie Groups	41
2.6.3	Local Coordinates of Matrix Lie Groups	46
2.6.4	Lie Algebra	46
2.6.5	Geometric Interpretation of Lie Group Representations	50
2.6.6	Actions on Lie Groups	57
2.7	Tangent Spaces, Vector Fields, and Integral Curves	69

2.7.1	Tangent Spaces . . . . .	69
2.7.2	Vector Fields, Flows, and Integral Curves . . . . .	71
2.8	The Exponential Map . . . . .	73
2.8.1	The Exponential of a Matrix . . . . .	74
2.8.2	Differential Equations . . . . .	75
2.8.3	The Natural Path in a Matrix Group . . . . .	76
2.8.4	Rigid Body Motion in Terms of Exponential Coordinates . . . . .	78
2.8.5	The Exponential Map of the Most Important Lie Groups . . . . .	79
2.8.6	Charts and Exponential Maps . . . . .	82
2.9	Local Coordinates and Velocity Transformation Matrices . . . . .	85
2.9.1	Velocity Transformation Matrices in Dynamics . . . . .	85
2.9.2	The Velocity Transformation Matrix in Terms of Exponential Coordinates . . . . .	86
2.10	Geometric Integrators . . . . .	88
	References . . . . .	89
<b>3</b>	<b>Rigid Body Kinematics . . . . .</b>	<b>91</b>
3.1	Translational Motion in $\mathbb{R}^3$ . . . . .	91
3.1.1	Spatial Linear Velocities . . . . .	93
3.2	Rotational Motion in $\mathbb{R}^3$ . . . . .	93
3.2.1	The Euler Angles . . . . .	94
3.2.2	The Rotation Matrix . . . . .	95
3.2.3	The Quaternion Representation . . . . .	97
3.2.4	Angular Velocity and Angular Acceleration . . . . .	98
3.2.5	The Relation Between Euler Angle Derivatives and Twists . . . . .	100
3.3	Rigid Body Transformations . . . . .	104
3.3.1	Vector Representation . . . . .	104
3.3.2	Singularities in the Representation . . . . .	106
3.3.3	Configuration States as Matrix Lie Groups . . . . .	108
3.3.4	The Special Euclidean Group . . . . .	109
3.3.5	Configuration Spaces as Subgroups of $SE(3)$ . . . . .	113
3.3.6	Local Coordinates . . . . .	120
	References . . . . .	123
<b>4</b>	<b>Kinematics of Manipulators on a Fixed Base . . . . .</b>	<b>125</b>
4.1	Static Kinematics . . . . .	126
4.1.1	Reference Frames . . . . .	126
4.1.2	Homogeneous Transformations . . . . .	129
4.1.3	Product of Exponentials Formula . . . . .	133
4.2	The Manipulator Twists . . . . .	135
4.3	Manipulator Velocities . . . . .	145
4.4	Manipulator Jacobian . . . . .	149
4.4.1	Body Geometric Jacobian . . . . .	150
4.4.2	Spatial Geometric Jacobian . . . . .	156
4.4.3	The Geometric Jacobian of the Manipulator Links . . . . .	161
4.4.4	Analytical Jacobian . . . . .	163

4.5	Configuration States . . . . .	164
4.5.1	Local Coordinates . . . . .	167
	References . . . . .	167
<b>5</b>	<b>Kinematics of Vehicle-Manipulator Systems . . . . .</b>	<b>169</b>
5.1	Configuration Space . . . . .	169
5.2	Velocity Transformation Matrices . . . . .	172
5.2.1	Twist and Position Variables . . . . .	172
5.2.2	Link Velocities . . . . .	173
5.2.3	The Geometric Jacobian . . . . .	178
5.2.4	Workspace Jacobian . . . . .	179
5.3	Configuration States . . . . .	181
5.3.1	Local Coordinates . . . . .	181
5.4	Some Simple Examples . . . . .	183
	References . . . . .	189
<b>6</b>	<b>Rigid Body Dynamics . . . . .</b>	<b>191</b>
6.1	Lagrangian Mechanics . . . . .	193
6.1.1	Kinetic Energy . . . . .	195
6.1.2	Potential Energy . . . . .	197
6.1.3	The Euler–Lagrange Equations of Motion . . . . .	197
6.1.4	The Dynamic Equations in Matrix Form . . . . .	199
6.2	Euler–Lagrange Equations for Rigid Body Motion . . . . .	199
6.2.1	Euler–Lagrange Equations in Matrix Form . . . . .	203
6.3	Full State Space Dynamics in Vector Form . . . . .	205
6.4	Lagrange Equations of Motion in Quasi-coordinates . . . . .	207
6.4.1	The Euler–Lagrange Equations in Matrix Form . . . . .	212
6.4.2	Local Parameterization . . . . .	213
6.4.3	The Most Important Configuration Spaces . . . . .	218
6.4.4	Other Formulations in Quasi-coordinates . . . . .	225
	References . . . . .	226
<b>7</b>	<b>Dynamics of Manipulators on a Fixed Base . . . . .</b>	<b>229</b>
7.1	Kinetic and Potential Energy in Multibody Systems . . . . .	229
7.2	Lagrangian Dynamics . . . . .	235
7.2.1	Robot Dynamics in Matrix Form . . . . .	236
7.2.2	Operational Space Approach . . . . .	238
7.3	Configuration States . . . . .	240
7.4	The Euler–Lagrange Equations of Motion in Quasi-coordinates . . . . .	241
7.5	Robot Dynamics in Matrix Form . . . . .	243
7.6	Local Parameterization . . . . .	244
	References . . . . .	245
<b>8</b>	<b>Dynamics of Vehicle-Manipulator Systems . . . . .</b>	<b>247</b>
8.1	The Dynamic Equations in Terms of Quasi-velocities . . . . .	248
8.2	The Dynamic Equations in Terms of Generalized Coordinates and Quasi-velocities . . . . .	252

8.2.1	Full State Space Dynamics in Vector Form . . . . .	258
8.2.2	Operational Space Approach . . . . .	259
8.3	Configuration States . . . . .	260
8.3.1	Local Parameterization . . . . .	266
8.3.2	Dynamic Structure of Vehicle-Manipulator Systems . . . . .	270
8.3.3	The Most Important Configuration Spaces . . . . .	271
8.3.4	Examples . . . . .	278
	References . . . . .	283
<b>9</b>	<b>Properties of the Dynamic Equations in Matrix Form . . . . .</b>	<b>285</b>
9.1	Misconceptions in the Literature . . . . .	286
9.2	The Boundedness and Skew-Symmetric Properties in Control . . . . .	288
9.2.1	Properties of the Dynamics in Matrix Form . . . . .	288
9.2.2	Robust Control . . . . .	290
9.2.3	PD Control Law . . . . .	292
9.3	Single Rigid Bodies . . . . .	292
9.3.1	The Boundedness Property . . . . .	293
9.3.2	The Skew-Symmetric Property . . . . .	294
9.4	Robotic Manipulators on a Fixed Base . . . . .	296
9.4.1	The Boundedness Property . . . . .	297
9.4.2	The Skew-Symmetric Property . . . . .	299
9.5	Vehicle-Manipulator Systems . . . . .	301
9.5.1	The Boundedness Property . . . . .	301
9.5.2	The Skew-Symmetric Property . . . . .	302
	References . . . . .	304
<b>10</b>	<b>Underwater Robotic Systems . . . . .</b>	<b>307</b>
10.1	Introduction . . . . .	307
10.1.1	Operating Under Water . . . . .	308
10.1.2	Underwater Vehicle-Manipulator Systems—A Brief Historical Overview . . . . .	310
10.1.3	Underwater Manipulators . . . . .	312
10.2	Dynamics of Underwater Vehicles . . . . .	313
10.2.1	Full State Space Dynamics in Vector Form . . . . .	319
10.3	AUV-Manipulator Dynamics . . . . .	320
10.3.1	Operational Space Approach . . . . .	321
10.4	Configuration States . . . . .	322
	References . . . . .	323
<b>11</b>	<b>Spacecraft-Manipulator Systems . . . . .</b>	<b>325</b>
11.1	Introduction . . . . .	325
11.1.1	Operating in Space . . . . .	326
11.1.2	Space Exploration . . . . .	329
11.1.3	Disturbances . . . . .	332
11.1.4	Actuators . . . . .	333
11.1.5	Coordinate Frames . . . . .	335

11.2 Free-Floating and Free-Flying Rigid Bodies . . . . .	336
11.2.1 Spacecraft Kinematics . . . . .	336
11.2.2 Spacecraft Dynamics . . . . .	336
11.3 Modeling of Free-Floating and Free-Flying Robots . . . . .	337
11.3.1 Kinematics of Spatial Vehicle-Manipulator Systems . . . . .	337
11.3.2 Dynamics of Spatial Vehicle-Manipulator Systems . . . . .	345
11.4 The Dynamically Equivalent Manipulator Approach . . . . .	348
11.4.1 Mathematical Formulation . . . . .	350
11.4.2 Configuration States . . . . .	352
References . . . . .	353
<b>12 Field Robots . . . . .</b>	<b>355</b>
12.1 Introduction . . . . .	355
12.1.1 Earth-Based Systems . . . . .	356
12.1.2 Space Robots . . . . .	357
12.1.3 Locomotion . . . . .	357
12.1.4 Mobility and Configuration Spaces . . . . .	359
12.1.5 Non-holonomic Motion . . . . .	360
12.2 Modeling of Wheeled Robots . . . . .	362
12.2.1 Chassis Kinematics . . . . .	362
12.2.2 Wheel Kinematics . . . . .	366
References . . . . .	368
<b>13 Robotic Manipulators Mounted on a Forced Non-inertial Base . . . . .</b>	<b>369</b>
13.1 Introduction . . . . .	369
13.1.1 Seaborne Platforms . . . . .	370
13.1.2 Active Heave Compensation . . . . .	370
13.1.3 Land Vehicles . . . . .	371
13.2 Dynamics of Manipulators on a Forced Base . . . . .	373
13.3 Motion Planning and Control . . . . .	375
13.3.1 Canceling the Inertial Forces . . . . .	375
13.3.2 Leveraging the Inertial Forces . . . . .	376
References . . . . .	377
<b>Appendix Implementation and Proofs . . . . .</b>	<b>379</b>
A.1 Computing the Partial Derivatives of the Inertia Matrix . . . . .	379
A.1.1 Computing the Partial Derivatives of $Ad_{g_{ij}}$ . . . . .	379
A.1.2 Computing the Jacobian and Its Partial Derivatives . . . . .	382
A.1.3 Implementation . . . . .	382
<b>Index . . . . .</b>	<b>385</b>

Vehicle-Manipulator Systems

Modeling for Simulation, Analysis, and Control

From, P.J.; Gravdahl, J.T.; Pettersen, K.Y.

2014, XXIV, 388 p. 52 illus., 33 illus. in color., Hardcover

ISBN: 978-1-4471-5462-4