

Assignment (Robotics I, Robotics) 2nd

(M2, M1, B4, B3, others: CIRCLE ONE)

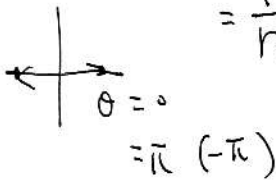
Major (Department)

Name(KANJI or English)

① prove the case of $S_\theta = 0$ for the Euler parameters formula

$$\begin{cases} \psi = \text{arbitrary} \\ \theta = 0 & \phi = \text{atan2}(R_{21}, R_{22}) - \psi \\ \theta = \pi & \phi = -\text{atan2}(R_{21}, R_{22}) + \psi \end{cases}$$

when $S_\theta = 0$
 $\gamma = 0 \rightarrow \gamma = 0 \rightarrow \theta = 0 \text{ or } \pi (-\pi)$



① When $\theta = 0$, $R_{21} = S_\phi C_\psi C_\psi + C_\phi S_\psi = S_\phi C_\psi + C_\phi S_\psi$

$R_{22} = -S_\phi C_\psi S_\psi + C_\phi C_\psi = -S_\phi S_\psi + C_\phi C_\psi$

$\tan(\phi + \psi) = \frac{\sin\phi \cos\psi + \cos\phi \sin\psi}{\cos\phi \cos\psi - \sin\phi \sin\psi} = \frac{R_{21}}{R_{22}}$

$\phi + \psi = \text{atan2}(R_{21}, R_{22})$
 $\phi = \text{atan2}(R_{21}, R_{22}) - \psi$

② about ψ , $R_{31} = -S_\theta C_\psi = 0$, $R_{32} = S_\theta S_\psi = 0 \Rightarrow$ any value of ψ is ok
 ψ is arbitrary

③ when $\theta = \pi$, $\cos\theta = -1$, $R_{21} = -S_\phi C_\psi + C_\phi S_\psi$

$R_{22} = -S_\phi S_\psi - C_\phi C_\psi$

$\tan(-(\phi - \psi)) = -\tan(\phi - \psi)$

$= -\left[\frac{\sin\phi \cos\psi - \cos\phi \sin\psi}{\cos\phi \cos\psi + \sin\phi \sin\psi} \right] = \frac{-R_{21}}{R_{22}}$

$\Rightarrow \phi - \psi = \text{atan2}(-R_{21}, R_{22}) = -\text{atan2}(R_{21}, R_{22})$

Thus $\phi = -\text{atan2}(R_{21}, R_{22}) + \psi$



${}^0R = \begin{bmatrix} 0 & 1 & 0 \\ 1 & 0 & 0 \\ 0 & 0 & -1 \end{bmatrix}$

$\theta = \text{atan2}(\pm 0, -1) = \pi (-\pi) \rightarrow S_\theta = 0 \rightarrow$ using the above $\theta = \pi$ case

$\begin{pmatrix} R_{13} = 0, R_{23} = 0 \\ R_{33} = -1 \\ R_{21} = 1, R_{22} = 0 \end{pmatrix}$

$\begin{cases} \psi = \text{arbitrary} \\ \theta = \pi, \\ \phi = -\text{atan2}(1, 0) + \psi = -\frac{\pi}{2} + \psi \end{cases}$