Robotics 2

Dynamic model of robots: Newton-Euler approach

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Approaches to dynamic modeling
(reprise)

energy-based approach (Euler-Lagrange) $\rightleftharpoons$ **Newton-Euler method (balance of forces/torques)**

energy-based approach (Euler-Lagrange)

- multi-body robot seen as a whole
- constraint (internal) reaction forces between the links are automatically eliminated: in fact, they do not perform work
- closed-form (symbolic) equations are directly obtained
- best suited for study of dynamic properties and **analysis** of control schemes

Newton-Euler method (balance of forces/torques)

- dynamic equations written separately for each link/body
- inverse dynamics in real time
  - equations are evaluated in a numeric and recursive way
  - best for **synthesis** (=implementation) of model-based control schemes
- by elimination of reaction forces and back-substitution of expressions, we still get closed-form dynamic equations (identical to those of Euler-Lagrange!)

Derivative of a vector in a moving frame

... from velocity to acceleration

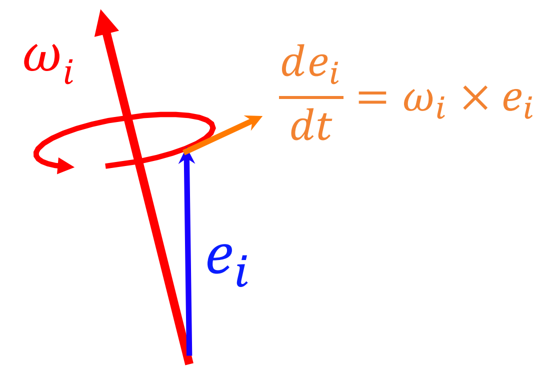
$$ {}^0v_i = {}^0R_i\,{}^iv_i \qquad\qquad {}^0\dot{R}_i = S({}^0\omega_i)\,{}^0R_i $$

$$ {}^0\dot{v}_i = {}^0a_i = {}^0R_i\,{}^ia_i = {}^0R_i\,{}^i\dot{v}_i + {}^0\dot{R}_i\,{}^iv_i $$

$$ = {}^0R_i\,{}^i\dot{v}_i + {}^0\omega_i \times {}^0R_i\,{}^iv_i = {}^0R_i\left({}^i\dot{v}_i + {}^i\omega_i \times {}^iv_i\right) $$

$$ \boxed{{}^ia_i = {}^i\dot{v}_i + {}^i\omega_i \times {}^iv_i} $$

derivative of "unit" vector



Dynamics of a rigid body

- Newton dynamic equation
  - balance: sum of forces = variation of linear momentum

$$\sum f_i = \frac{d}{dt}(m v_c) = m \dot{v}_c$$

- Euler dynamic equation
  - balance: sum of torques = variation of angular momentum

$$\sum \mu_i = \frac{d}{dt}(I\omega) = I\dot{\omega} + \frac{d}{dt}\left(R\bar{I}R^T\right)\omega = I\dot{\omega} + \left(\dot{R}\bar{I}R^T + R\bar{I}\dot{R}^T\right)\omega$$

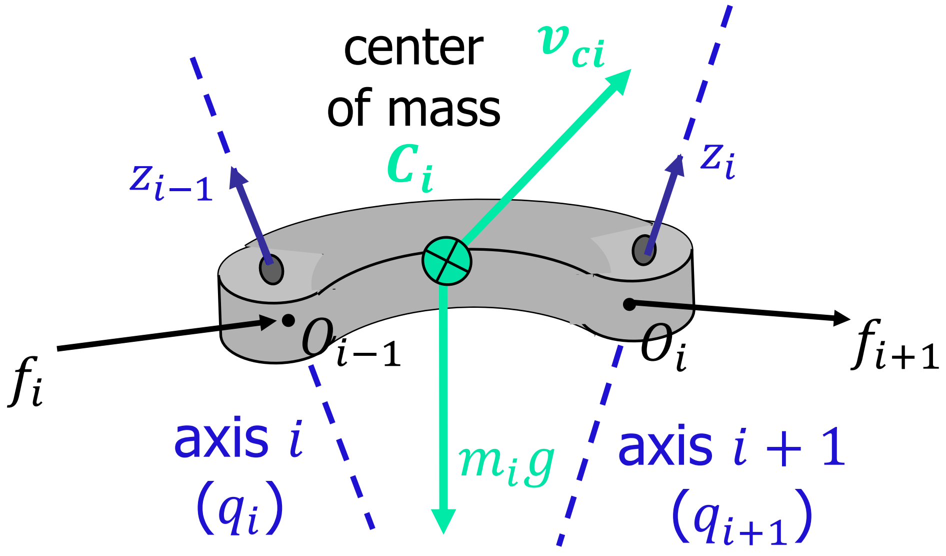
$$= I\dot{\omega} + S(\omega)R\bar{I}R^T\omega + R\bar{I}R^T S^T\cancel{(\omega)}\omega = I\dot{\omega} + \omega \times I\omega$$

- principle of action and reaction
  - forces/torques: applied by body i to body $i+1$

    = – applied by body $i+1$ to body i

Newton-Euler equations - 1

link i



FORCES

f_i force applied from link $i-1$ on link i

f_{i+1} force applied from link i on link $i+1$

$m_i g$ gravity force

all vectors expressed in the same RF (better RF$_i$)

Newton equation

$$\boxed{f_i - f_{i+1} + m_i g = m_i a_{ci}}$$

N

linear acceleration of C_i

Newton-Euler equations - 2

link i

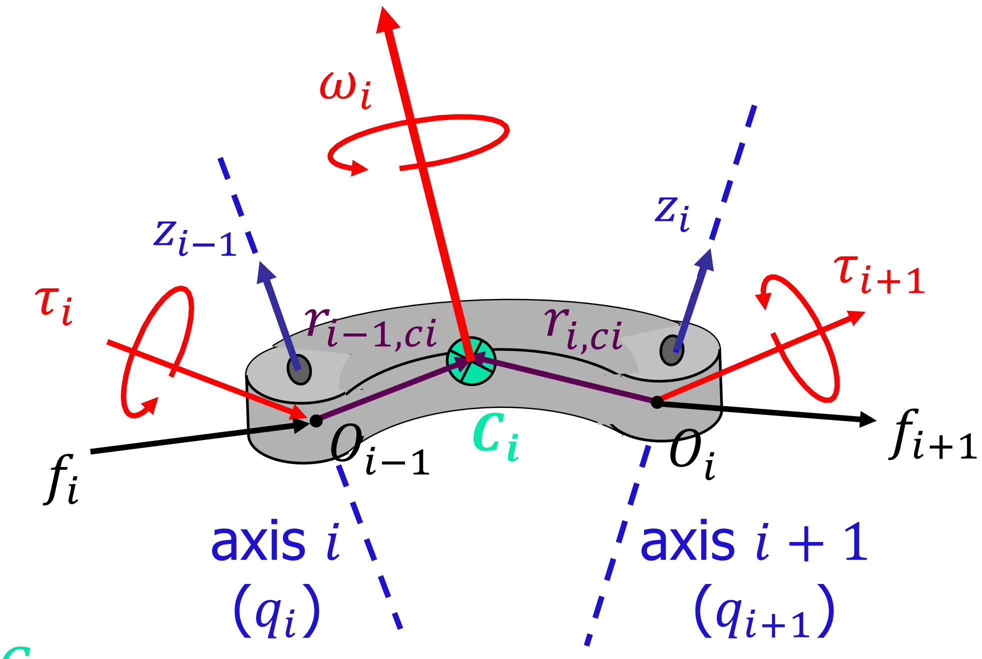
TORQUES

τ_i torque applied
from link $(i-1)$ on link i

τ_{i+1} torque applied
from link i on link $(i+1)$

$f_i \times r_{i-1,ci}$ torque due to f_i w.r.t. C_i

$-f_{i+1} \times r_{i,ci}$ torque due to $-f_{i+1}$ w.r.t. C_i



gravity force gives
no torque at C_i

all vectors expressed in
the same RF (RF_i !!)

Euler equation

$$\boxed{\tau_i - \tau_{i+1} + f_i \times r_{i-1,ci} - f_{i+1} \times r_{i,ci} = I_i \dot{\omega}_i + \omega_i \times (I_i \omega_i)}$$

E

angular acceleration of body i

Forward recursion

Computing velocities and accelerations

- "moving frames" algorithm (as for velocities in Lagrange)
- wherever there is no leading superscript, it is the same as the subscript $(\omega_i = {}^i\omega_i)$
- for simplicity, only revolute joints
  (see textbook for the more general treatment)

initializations

$$\omega_i = {}^{i-1}R_i^T \left[\omega_{i-1} + \dot{q}_i z_{i-1}\right] \qquad \leftarrow \omega_0$$

$$\begin{aligned} \dot{\omega}_i &= {}^{i-1}R_i^T \left[\dot{\omega}_{i-1} + \ddot{q}_i z_{i-1} - \dot{q}_i z_{i-1} \times (\omega_{i-1} + \dot{q}_i z_{i-1})\right] \\ &= {}^{i-1}R_i^T \left[\dot{\omega}_{i-1} + \ddot{q}_i z_{i-1} + \dot{q}_i \omega_{i-1} \times z_{i-1}\right] \qquad \leftarrow \dot{\omega}_0 \end{aligned}$$

AR

$$a_i = {}^{i-1}R_i^T a_{i-1} + \dot{\omega}_i \times {}^i r_{i-1,i} + \omega_i \times (\omega_i \times {}^i r_{i-1,i}) \qquad \leftarrow a_0 - {}^0g$$

$$a_{ci} = a_i + \dot{\omega}_i \times r_{i,ci} + \omega_i \times (\omega_i \times r_{i,ci})$$

the gravity force term can be skipped in Newton equation, if added here

Backward recursion

Computing forces and torques

F/TR

from N_i $\longrightarrow$ to N_{i-1}

eliminated, if inserted in forward recursion (i=0)

initializations

$$f_i = f_{i+1} + m_i(a_{ci} - \cancel{{}^i g}) \quad \longleftarrow f_{N+1}$$

$$\tau_{N+1} \downarrow$$

$$\tau_i = \tau_{i+1} - f_i \times (r_{i-1,i} + r_{i,c_i}) + f_{i+1} \times r_{i,c_i} + I_i \dot{\omega}_i + \omega_i \times (I_i \omega_i)$$

from E_i $\longrightarrow$ to E_{i-1}

at each step of this recursion, we have two vector equations ($N_i + E_i$) at the joint providing f_i and τ_i: these contain ALSO the reaction forces/torques at the joint axis ⇒ they should be "projected" next along/around this axis

FP

$$u_i = \begin{cases} f_i^T \, {}^i z_{i-1} + \eta_i \dot{q}_i & \text{for prismatic joint} \\ \tau_i^T \, {}^i z_{i-1} + \eta_i \dot{q}_i & \text{for revolute joint} \end{cases} \Rightarrow \boxed{N \text{ scalar equations}} \text{ at the end}$$

$\uparrow$

generalized forces (in rhs of Euler-Lagrange eqs)

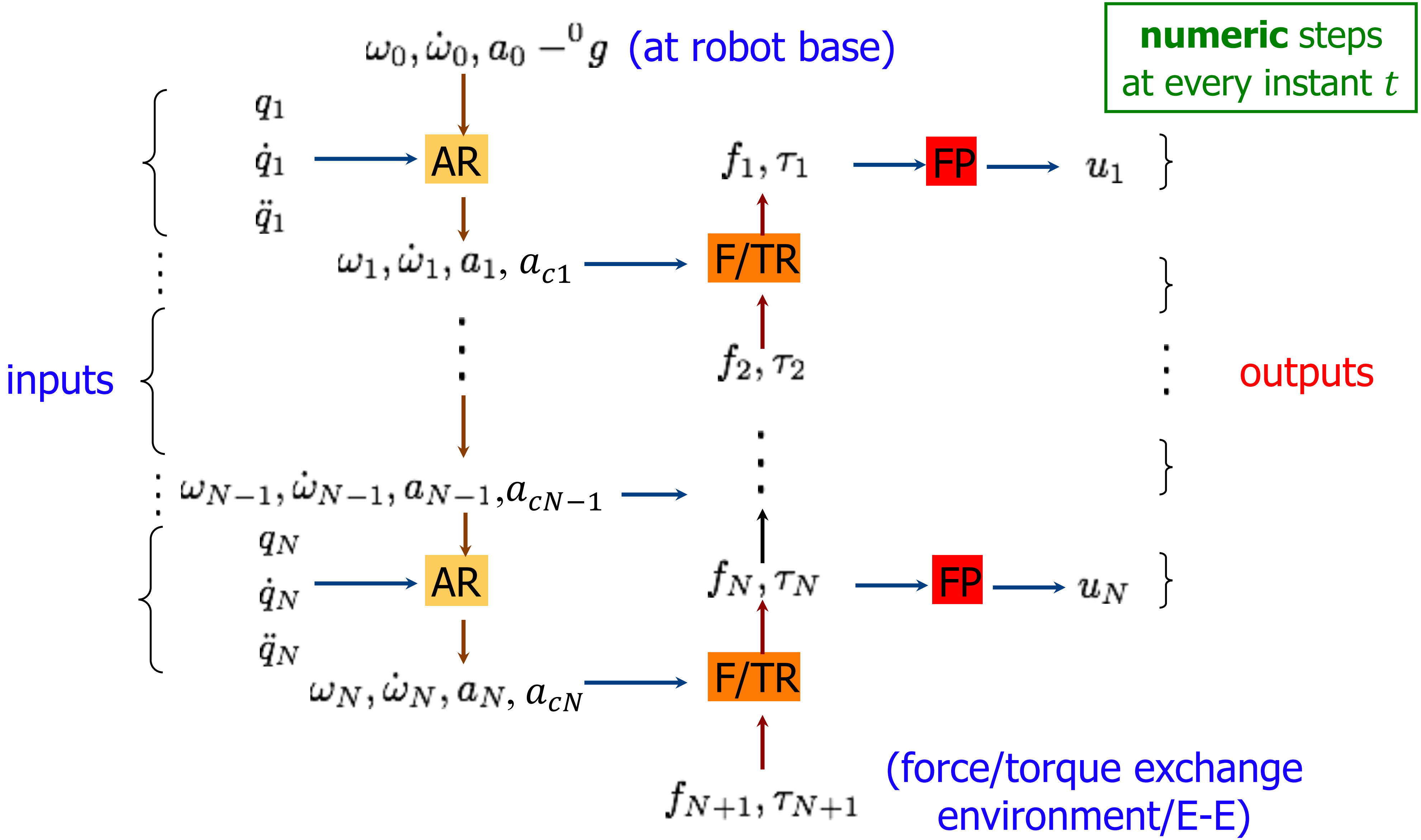
add here dissipative terms (here viscous friction only)

Comments on Newton-Euler method

- the previous forward/backward recursive formulas can be evaluated in symbolic or numeric form
  - symbolic
    - substituting expressions in a recursive way
    - at the end, a closed-form dynamic model is obtained, which is identical to the one obtained using Euler-Lagrange (or any other) method
    - there is no special convenience in using N-E in this way
  - numeric
    - substituting numeric values (numbers!) at each step
    - computational complexity of each step remains constant ⇒ grows in a linear fashion with the number N of joints ($O(N)$)
    - strongly recommended for real-time use, especially when the number N of joints is large

Newton-Euler algorithm

efficient computational scheme for inverse dynamics



Matlab (or C) script

general routine $NE_\alpha(\mathrm{arg}_1, \mathrm{arg}_2, \mathrm{arg}_3)$

- data file (of a specific robot)
  - number N and types $\sigma = \{0,1\}^N$ of joints (revolute/prismatic)
  - table of DH kinematic parameters
  - list of ALL dynamic parameters of the links (and of the motors)
- input
  - vector parameter $\alpha = \{{}^0g, 0\}$ (presence or absence of gravity)
  - three ordered vector arguments
    - typically, samples of joint position, velocity, acceleration taken from a desired trajectory
- output
  - generalized force u for the complete inverse dynamics
  - … or single terms of the dynamic model

Examples of output

- complete inverse dynamics

$$u = NE_{^0g}(q_d, \dot{q}_d, \ddot{q}_d) = M(q_d)\ddot{q}_d + c(q_d, \dot{q}_d) + g(q_d) = u_d$$

- gravity terms

$$u = NE_{^0g}(q, 0, 0) = g(q)$$

- centrifugal and Coriolis terms

$$u = NE_0(q, \dot{q}, 0) = c(q, \dot{q})$$

- i-th column of the inertia matrix

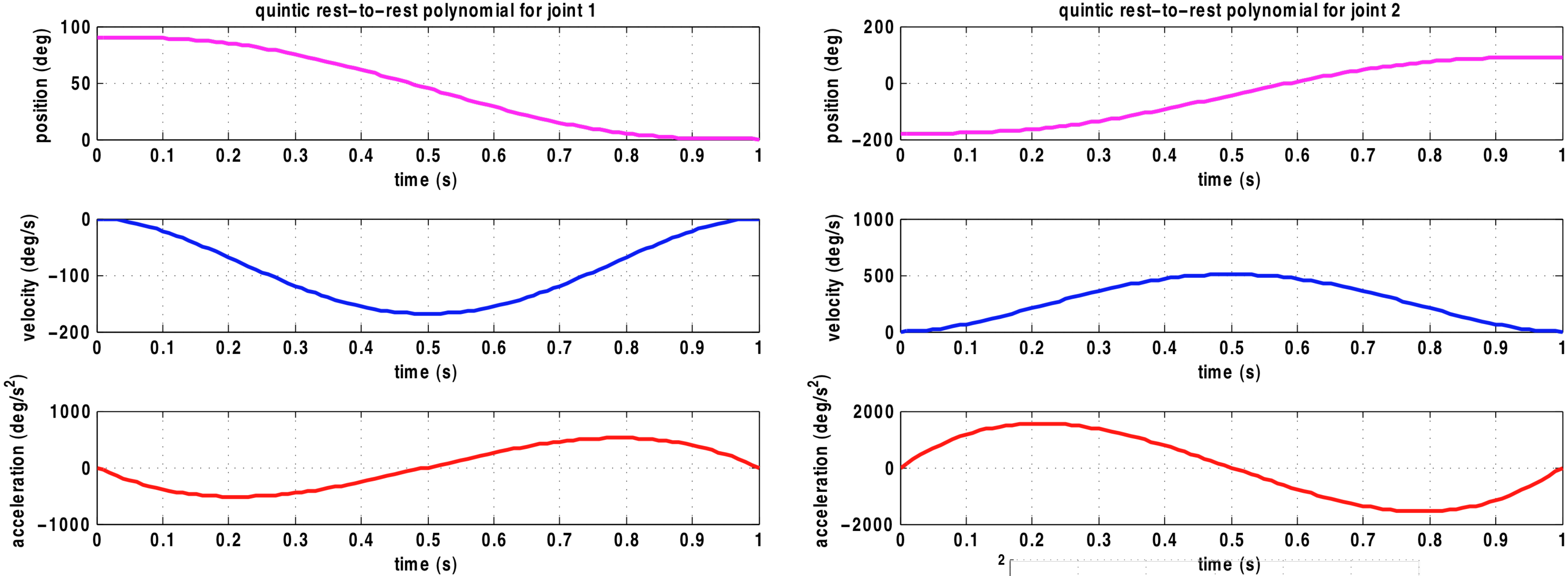
$$u = NE_0(q, 0, e_i) = M_i(q)$$

e_i = i-th column of identity matrix

- generalized momentum

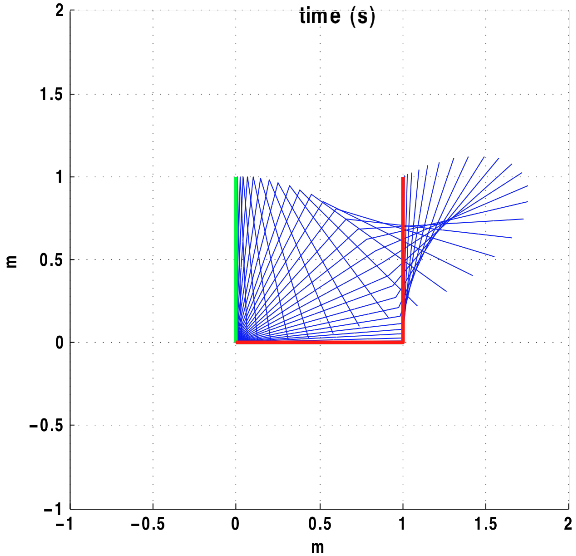
$$u = NE_0(q, 0, \dot{q}) = M(q)\dot{q} = p$$

Inverse dynamics of a 2R planar robot



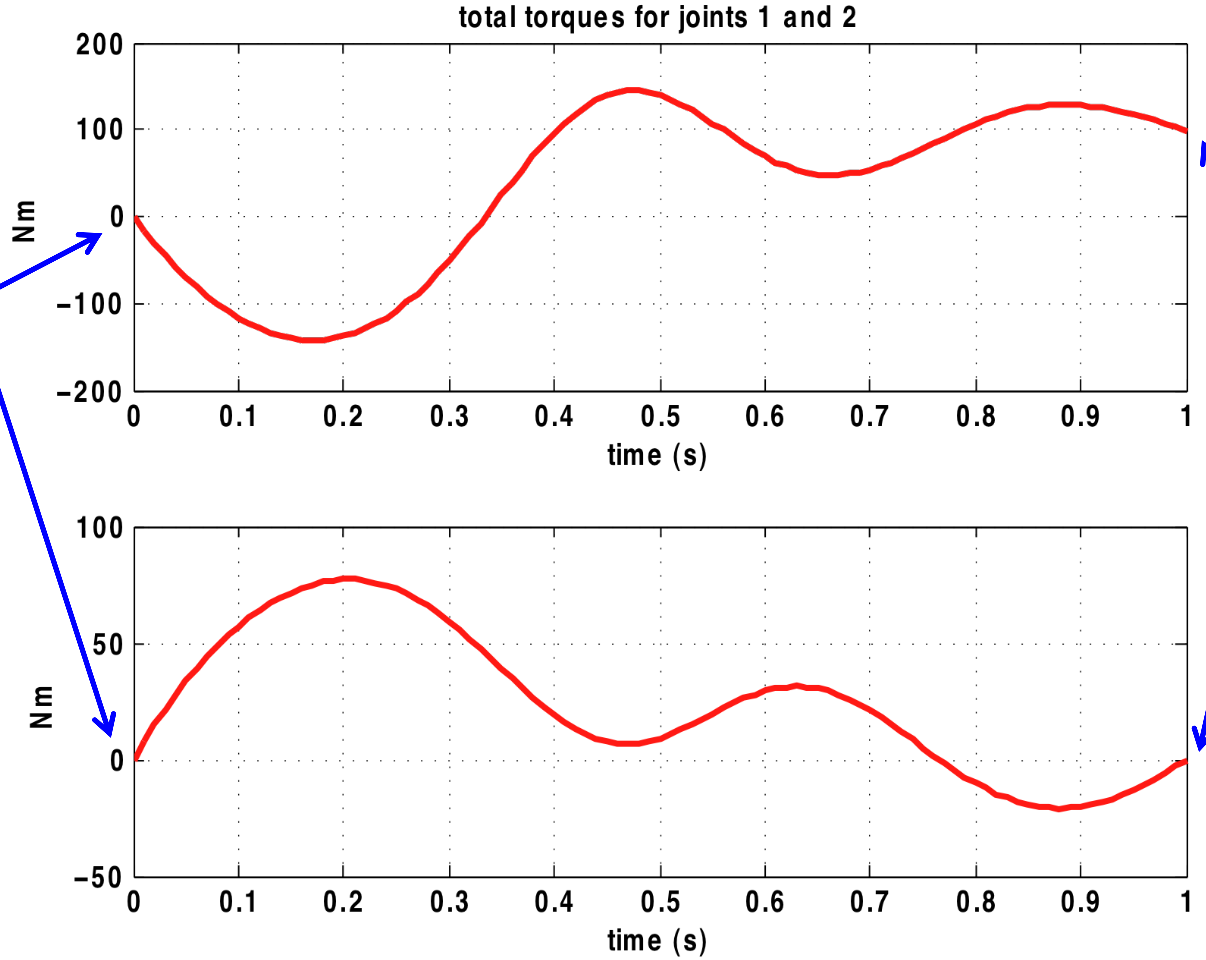
desired (smooth) joint motion:
quintic polynomials for q_1, q_2 with
zero vel/acc boundary conditions
from (90°, -180°) to (0°, 90°) in $T = 1$ s

$\Leftrightarrow$



Inverse dynamics of a 2R planar robot

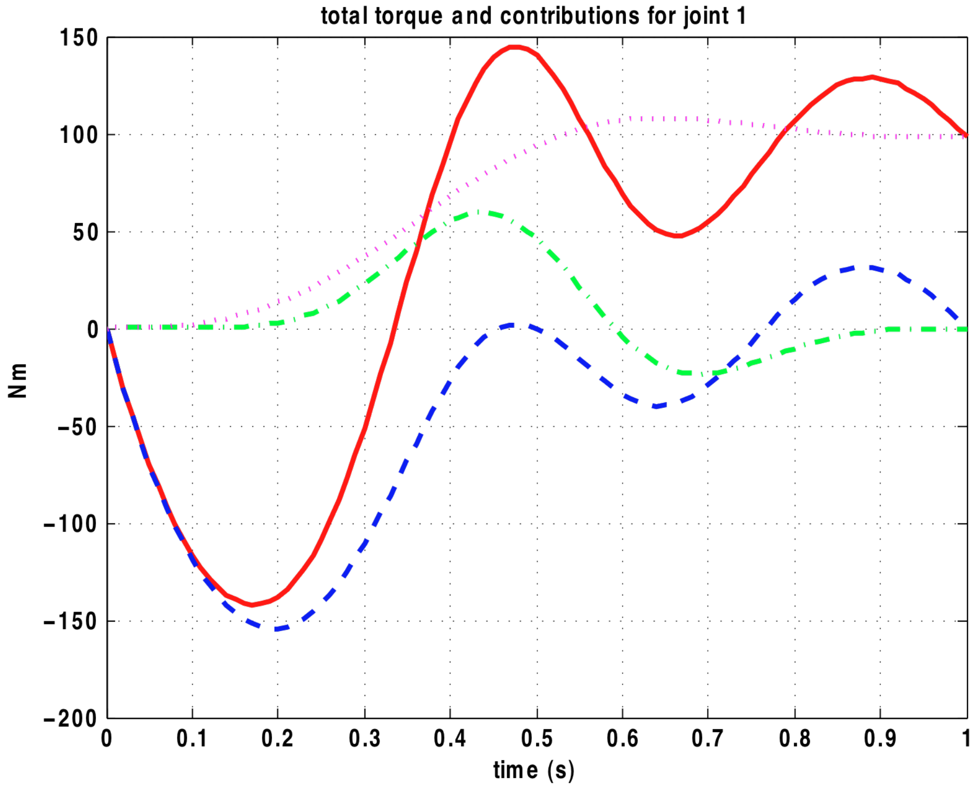
zero
initial torques =
free equilibrium
configuration
+
zero initial
accelerations

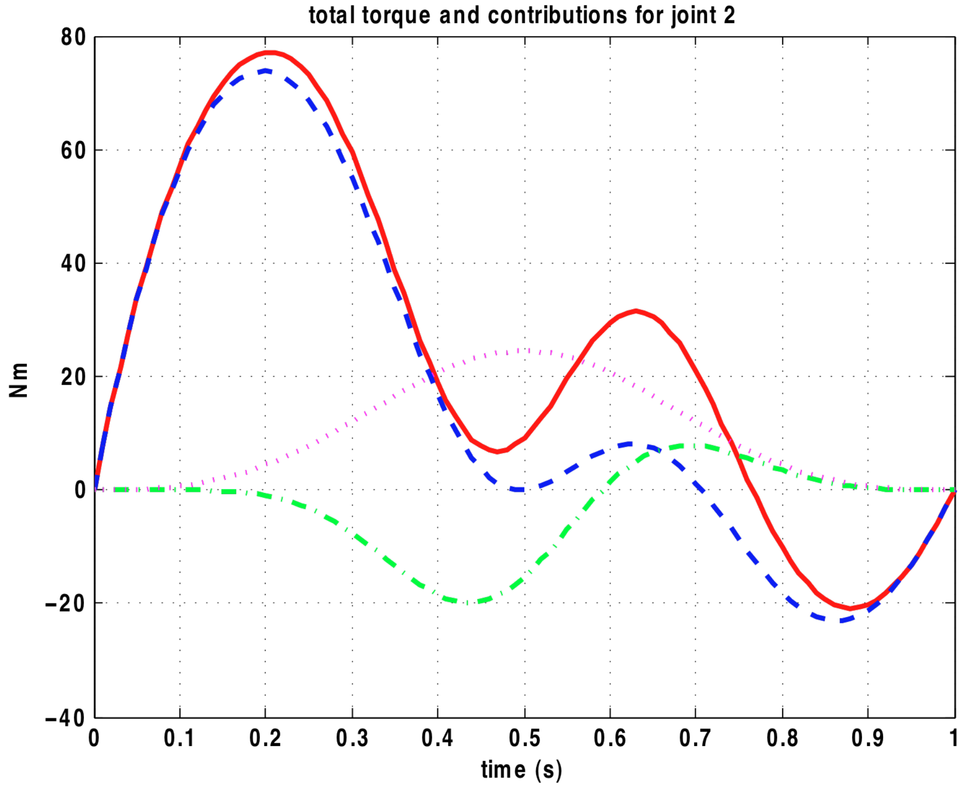


final torques
$u_1 \neq 0, u_2 = 0$
balance
link weights
in final (0°, 90°)
configuration

motion in vertical plane (under gravity)
both links are thin rods of uniform mass $m_1 = 10$ kg, $m_2 = 5$ kg

Inverse dynamics of a 2R planar robot





torque contributions at the two joints for the desired motion

—— = total, - - - - = inertial

- · - · - = Coriolis/centrifugal, ········· = gravitational

Use of NE routine for simulation
direct dynamics

- numerical integration, at current state $(q,\dot{q})$, of

$$\ddot{q} = M^{-1}(q)[u - (c(q,\dot{q}) + g(q))] = M^{-1}(q)[u - n(q,\dot{q})]$$

- Coriolis, centrifugal, and gravity terms

$$n = NE_{^0g}(q,\dot{q},0) \qquad \text{complexity } O(N)$$

- i-th column of the inertia matrix, for $i = 1,..,N$

$$M_i = NE_0(q,0,e_i) \qquad O(N^2)$$

- numerical inversion of inertia matrix

$$InvM = \text{inv}(M) \qquad O(N^3)$$

but with small coefficient

- given u, integrate acceleration computed as

$$\ddot{q} = InvM * [u - n] \quad \Rightarrow$$

new state $(q,\dot{q})$
and repeat over time ...