
Contents

Preface	xv
Author Biography	xxi
 I Preliminary Studies	 1
1 Introduction	3
1.1 What is a Robot	3
1.1.1 Robot Definitions	4
1.1.2 The History of Robotics	5
1.2 Robot Components	5
1.2.1 Links	7
1.2.2 Joints	8
1.2.3 Kinematic Chains	10
1.3 Robot Degrees of Freedom	11
1.4 Robot Classification	15
1.4.1 Serial Robots	16
1.4.2 Parallel Robots	19
1.4.3 Hybrid Structures	23
1.4.4 Cable-Driven Parallel Robots	24
1.5 Aims and Scope of the Book	27
Exercises	30
Problems	31
 2 Motion Representation	 38
2.1 Introduction	38
2.2 Spatial Motion Representation	39
2.2.1 Position of a point	40
2.2.2 Orientation of a Rigid Body	40
2.2.3 Rotation Matrix	41
2.2.4 Euler Angles	47
2.3 Rigid Body's Pose	56
2.4 Homogeneous Transformation	58
2.4.1 Homogeneous Coordinates	58
2.4.2 Homogeneous Transformation Matrix	59
2.4.3 Homogeneous Transformation Arithmetic	61
Problems	66
 3 Advanced Representations	 70
3.1 Introduction to Screw Theory	70
3.2 Orientation Representation	71

3.2.1	Screw Representation	72
3.2.2	Quaternion	75
3.3	Screw Representation for Motion	78
3.4	Linear and Angular Velocities	80
3.4.1	Angular Velocity of a Rigid Body	81
3.4.2	Angular Velocity and the Rate of Rotation Matrix	81
3.4.3	Angular Velocity and Rate of Euler Angles	83
3.4.4	Angular Velocity and Rate of Quaternion	83
3.4.5	Linear Velocity of a Point	85
3.5	Screw Coordinates	87
3.6	Linear and Angular Accelerations	91
3.6.1	Angular Acceleration of a Rigid Body	91
3.6.2	Linear Acceleration of a Point	92
	Problems	93

II Kinematics 97

4	Kinematic Analysis	99
4.1	Introduction	99
4.2	Parallel Robot Types	100
4.3	Loop Closure Method	102
4.4	Case Study I: Planar Cable Robot	104
4.4.1	Mechanism Description	104
4.4.2	Geometry of the Manipulator	105
4.4.3	Inverse Kinematics	105
4.4.4	Forward Kinematics	106
4.4.5	Simulations	108
4.5	Case Study II: Shoulder Manipulator	109
4.5.1	Mechanism Description	110
4.5.2	Geometry of the Manipulator	111
4.5.3	Inverse Kinematics	113
4.5.4	Forward Kinematics	114
4.5.5	Simulations	115
4.6	Case Study III: Stewart–Gough Platform	116
4.6.1	Mechanism Description	117
4.6.2	Geometry of the Manipulator	117
4.6.3	Inverse Kinematics	119
4.6.4	Forward Kinematics	119
4.6.5	Simulations	127
	Problems	134
5	Jacobian Matrix and Singularity	149
5.1	Introduction	149
5.2	Jacobian Matrices of a Parallel Manipulator	151
5.3	Jacobian Matrix Derivation	152
5.4	Singularity Analysis	153
5.4.1	Inverse Kinematic Singularity (Type I)	154
5.4.2	Forward Kinematic Singularity (Type II)	154
5.4.3	Combined Kinematic Singularity (Type III)	155
5.4.4	Singularity Avoidance	155

5.5	Case Study I: Planar Cable Robot	156
5.5.1	Velocity Loop Closure	156
5.5.2	Singularity Analysis	159
5.5.3	Sensitivity Analysis	159
5.6	Case Study II: Shoulder Manipulator	160
5.6.1	Velocity Loop Closure	161
5.6.2	Singularity Analysis	163
5.7	Case Study III: Stewart–Gough Platform	165
5.7.1	Velocity Loop Closure	165
5.7.2	Singularity Analysis	167
	Problems	170
6	Jacobian Matrix: Mappings & Characteristics	176
6.1	Introduction	176
6.2	Static Forces in Parallel Manipulators	178
6.2.1	Free-Body Diagram Approach	179
6.2.2	Virtual Work Approach	179
6.2.3	Case Study I: Planar Cable Robot	181
6.2.4	Case Study II: Shoulder Manipulator	183
6.2.5	Case Study III: Stewart–Gough Platform	185
6.3	Jacobian Matrix: Intrinsic Characteristics	187
6.3.1	Dexterity Ellipsoid	187
6.3.2	From Singularity to Isotropy	189
6.3.3	Dexterity Measure	191
6.3.4	Manipulability Measure	193
6.3.5	Global Measures	195
6.4	Stiffness Analysis	196
6.4.1	Stiffness Matrix	198
6.4.2	Stiffness Ellipsoid	200
6.4.3	Case Study I: Planar Cable Robot	201
6.4.4	Case Study II: Shoulder Manipulator	203
6.4.5	Case Study III: Stewart–Gough Platform	206
6.5	Inverse Problems	209
6.5.1	Inverse Velocity Problem	209
6.5.2	Inverse Force Problem	210
6.6	Redundancy Resolution	211
6.6.1	Problem Formulation	212
6.6.2	Lagrange and Karush–Kuhn–Tucker Multipliers	215
6.6.3	Iterative Solutions	218
6.6.4	Numerical Methods	219
6.6.5	An Iterative-Analytical Method	221
	Problems	224

III Dynamics 229

7	Dynamic Analysis: Newton-Euler Approach	231
7.1	Introduction	231
7.2	Dynamics of Rigid Bodies: A Review	233
7.2.1	Center of Mass	233
7.2.2	Moments of Inertia	235

7.2.3	Linear and Angular Momentum	236
7.2.4	Kinetic Energy	237
7.2.5	Newton–Euler Laws	238
7.3	Newton–Euler Formulation	239
7.4	Case Study I: Planar Cable Robot	240
7.4.1	Acceleration Analysis	241
7.4.2	Dynamic Formulation of the Limbs	242
7.4.3	Dynamic Formulation of the Moving Platform	245
7.5	Case Study II: Stewart–Gough Platform	246
7.5.1	Acceleration Analysis	247
7.5.2	Dynamic Formulation of the Limbs	250
7.5.3	Dynamic Formulation of the Moving Platform	254
7.5.4	Closed-Form Dynamics	255
	Problems	259
8	Dynamic Analysis: Euler-Lagrange Approach	263
8.1	Introduction	263
8.2	Euler-Lagrange Formulation	264
8.2.1	Generalized Coordinates and Forces	265
8.2.2	Euler-Lagrange Equations of the Second Kind	267
8.2.3	Euler-Lagrange Equations of the First Kind	269
8.3	Properties of Dynamic Formulations	270
8.3.1	Properties of Mass Matrix	272
8.3.2	Christoffel Matrix	273
8.3.3	Linearity in Parameters	277
8.4	Case Study I: Planar Cable Robot	278
8.4.1	Dynamic Formulation of the Limbs	280
8.4.2	Dynamic Formulation of the Moving Platform	284
8.4.3	Dynamic Formulation of the Whole Manipulator	285
8.5	Case Study II: Stewart–Gough Platform	287
8.5.1	Dynamic Formulation of the Limbs	287
8.5.2	Dynamic Formulation of the Moving Platform	293
8.5.3	Dynamic Formulation of the Whole Manipulator	294
	Problems	295
9	Dynamic Analysis: Virtual Work Approach	297
9.1	Introduction	297
9.2	D'Alembert's Principle	298
9.3	Principle of Virtual Work	299
9.4	Closed-Form Formulation	303
9.5	Case Study I: Planar Cable Robot	305
9.5.1	Implicit Dynamics	305
9.5.2	Formulation Verification	307
9.6	Case Study II: Stewart–Gough Platform	308
9.7	Case Study III: The 3UPU Manipulator	311
9.7.1	Manipulator Structure and Kinematics	311
9.7.2	Jacobian Analysis	313
9.7.3	Acceleration Analysis	316
9.7.4	Implicit Dynamics	318
9.7.5	Closed-Form Formulation	318
	Problems	320

10 Dynamic Simulation and Calibration	322
10.1 Introduction	322
10.2 Motion Planning	323
10.2.1 Cubic Polynomials	324
10.2.2 Cubic Polynomials with Via Points	326
10.2.3 Quintic Polynomials	329
10.2.4 Linear Trajectory with Parabolic Blends	332
10.2.5 Trajectory Planning in Joint Space	339
10.3 Motion Simulation	339
10.3.1 Forward Dynamics	340
10.3.2 Inverse Dynamics	342
10.4 Case Study I: Planar Cable Robot	343
10.4.1 Forward Dynamics Simulations	344
10.4.2 Closed-Loop Dynamics Simulations	347
10.4.3 Inverse Dynamics Simulation	350
10.5 Case Study II: Stewart–Gough Platform	352
10.5.1 Forward Dynamics Simulation	352
10.5.2 Closed-Loop Dynamics Simulation	355
10.5.3 Inverse Dynamics Simulation	358
10.6 Dynamic Calibration	364
10.6.1 Linear Regression Models	365
10.6.2 Least Squares Method	366
10.6.3 Evaluation of Calibrated Model	367
Problems	368
IV Control	373
11 Linear Motion Control	375
11.1 Introduction	375
11.2 Controller Topologies	377
11.2.1 Motion Control in Task Space	377
11.2.2 Motion Control in Joint Space	379
11.2.3 Topology Selection	380
11.3 Linear Control: Concepts and Methods	381
11.3.1 Magic of Feedback	382
11.3.2 PD Control	384
11.3.3 PID Control	388
11.3.4 Performance Limitations	389
11.3.5 Feed-Forward Control	391
11.4 PD Control in Parallel Robots	392
11.5 Multivariable PID Control	394
11.6 Case Study I: Planar Cable Robot	395
11.6.1 Decentralized PD Control	395
11.6.2 Multivariable PID Control	402
11.7 Case Study II: Stewart Gough Platform	408
11.7.1 Decentralized PD Control	408
11.7.2 Multivariable PID Control	415
Problems	422

12 Multivariable and Nonlinear Control	424
12.1 Introduction	424
12.2 Multivariable Control with Feed-Forward	425
12.3 Inverse Dynamics Control	427
12.4 Partial Feedback Linearization	429
12.5 Robust and Adaptive Control	432
12.5.1 Model Uncertainty	433
12.5.2 Robust Inverse Dynamics Control	434
12.5.3 Chattering Mitigation	439
12.5.4 Adaptive Inverse Dynamics Control	441
12.6 Summary of Motion Control Techniques	445
12.7 Case Study I: Planar Cable Robot	447
12.7.1 Basic PID Control	448
12.7.2 PID Control with Feed-Forward	449
12.7.3 Inverse Dynamics Control	452
12.7.4 Partial Feedback Linearization	452
12.7.5 Robust Inverse Dynamics Control	454
12.7.6 Adaptive Inverse Dynamics Control	456
12.8 Case Study II: Stewart–Gough Platform	459
12.8.1 Basic PID Control	459
12.8.2 Feed-Forward Control	461
12.8.3 Inverse Dynamics Control	465
12.8.4 Partial Feedback Linearization	467
12.8.5 Robust Inverse Dynamics Control	469
Problems	471
13 Force Control	474
13.1 Introduction	474
13.2 Controller Topologies	476
13.2.1 Cascade Control	477
13.2.2 Force Feedback in the Outer Loop	478
13.2.3 Force Feedback in the Inner Loop	481
13.3 Stiffness Control	484
13.3.1 Single-Degree-of-Freedom Stiffness Control	485
13.3.2 General Stiffness Control	488
13.3.3 Case Study I: Planar Cable Robot	492
13.3.4 Case Study II: Stewart–Gough Platform	495
13.4 Direct Force Control	503
13.4.1 Case Study I: Planar Cable Robot	508
13.4.2 Case Study II: Stewart–Gough Platform	511
Problems	517
14 Impedance Control	520
14.1 Introduction	520
14.2 Definition of Impedance	521
14.3 Impedance Control Concept	524
14.3.1 Automated Fish Fillet Production	524
14.3.2 Flight Simulator Yoke	525
14.4 Impedance Control Structure	527
14.5 Special Case in Impedance Control	529
14.6 Case Study I: Planar Cable Robot	530

14.7 Case Study II: Stewart–Gough Platform 535

Problems 543

V Appendices **547**

A Appendix A: Linear Algebra **549**

A.1 Vectors and Matrices 549

A.2 Vectors and Matrices Arithmetic 550

A.3 Eigenvalues and Singular Values 552

A.4 Pseudo-Inverse 553

 A.4.1 Pseudo-Inverse Properties 554

 A.4.2 Linear Inverse Problem 554

A.5 Kronecker Product 556

B Appendix B: Nonlinear Control Review **558**

B.1 Dynamical Systems 558

B.2 Stability Definitions 558

B.3 Lyapunov Stability 560

B.4 Krasovskii–Lasalle Theorem 563

Bibliography **565**

Index **581**