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Introduction to Robotics (SS2013)

Assignment #1

Due: 10.04.2014, 14.00

Task 1.1: (8 points) A pyramid (square base $AB = BC = CD = DA = 10cm$; plumb-line $ME = 30cm$, with vertex E located at the top and point M located at the center of the base) is held by a robot so that its square base $ABCD$ is located in the xy-plane of a cartesian world coordinate frame M_{xyz}, with point M at its origin, the edges AB and CD parallel to the x-axis and the edged BC and AD parallel to the y-axis. Attached to the pyramid is an object coordinate frame M_{uvw}, which initially coincides with M_{xyz}.

1.1.1: Determine the locations of the vertices A through E, after the following sequence of rotations has been performed by the robot: 1. Rotation by $+45^o$ around M_w; 2. Rotation by $+30^o$ around M_u; 3. Rotation by -30^o around M_v.

1.1.2: Same sequence of rotations, but using the rotation axes M_z, M_x and M_y instead.

Task 1.2: (6 points) Given are three frames A, B and C as well as the following two homogeneous transformations:

$$ {}^{A}T_{B} = \begin{bmatrix} \sqrt{3}/2 & -1/2 & 0 & 2 \\ 1/2 & \sqrt{3}/2 & 0 & 1 \\ 0 & 0 & 1 & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix} $$

and

$$ {}^{B}T_{C} = \begin{bmatrix} 1/\sqrt{2} & 1/\sqrt{2} & 0 & 1 \\ -1/\sqrt{2} & 1/\sqrt{2} & 0 & 1 \\ 0 & 0 & 1 & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix} $$

1.2.1: Can the interpretation of the transformation ${}^{A}T_{C}$ be assumed to be unambiguous?

1.2.2: Visualize the three coordinate systems with a tool of your choice

Task 1.3: (3 points) Give three examples of Euler angles (ϕ, θ, ψ) and interpret their geometric meaning.

Task 1.4: (3 points) There are 12 possible sequences of rotations with Euler-angles around the axes (see slide 25). Explain why there are exactly 12! (hint: this can be answered in one sentence and one simple calculation) .