

5ELEN018W - Tutorial 7 Exercises: Forward Kinematics

1 Combined Transformations

A point P with coordinates $[7, 3, 1]^T$ is attached to a frame F which is subject to the following 3 successive transformations relative to the reference frame F_{xyz} :

1. Rotation of 90° about the z -axis.
2. Followed by a rotation of 90° about the y -axis.
3. Followed by a translation of $[4, -3, 7]$.

Find manually (using a calculator, you could use one of the software implemented calculators) the coordinates of the point relative to the reference frame after all the transformations have taken place.

Verify your calculations by using matlab and doing the same calculations using matrices.

Hints: See the lecture 3 slides. The order of the matrices written (calculated) is the opposite of the order of transformations performed. The result should calculate to $[5, 4, 10, 1]$.

2 DH Matrix Derivation

Consider the following DH table:

Joint	θ	r	d	α
1	θ	r	d	α

1. Use Matlab to derive the DH matrix by applying the 4 basic transformations shown on the left hand side of Equation (6) of the last lecture.
Use symbolic Matlab (i.e. use the command `syms theta r d alpha` before creating the 4 basic matrix transformations).
2. Check that your calculated DH matrix matches with the one shown on the right hand side of Equation (6) of the last lecture slides.

3 DH Matrix

Consider a 2-joint robot with the following DH table:

Joint	θ	r	d	α
1	θ_1	r_1	d_1	α_1
2	θ_2	r_2	d_2	α_2

Determine the position of the robot's end-effector. Use symbolic Matlab for the calculations.

4 3-DOF Robot - Forward Kinematics Problem

Consider the 3-DOF robot shown in Figure 1. Its DH table is given by:

Joint	θ	r	d	α
1	θ_1	r_1	0	0
2	$90 + \theta_2$	0	0	90
3	θ_3	0	d_3	0

Determine the position of the robot's end-effector. Use symbolic Matlab for the calculations.

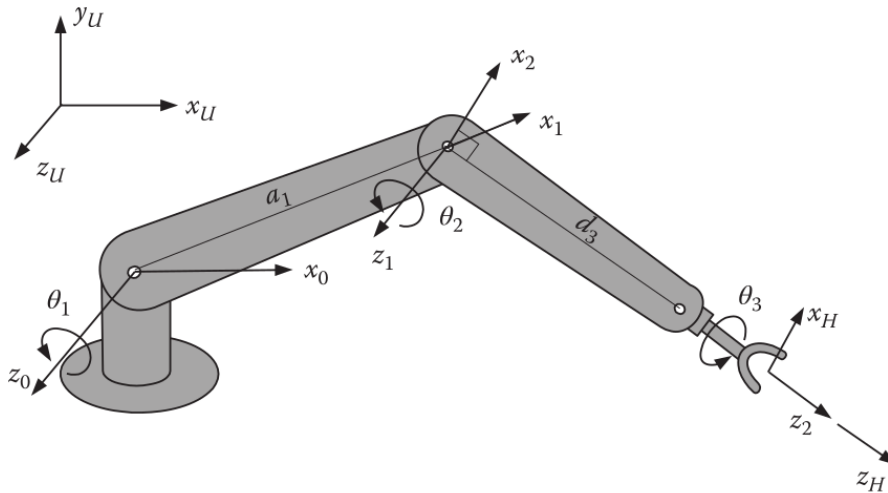


Figure 1: The 3-DOF robot of Exercise 4.

5 Matlab Programming

Write a Matlab function (see Week 1) which accepts 4 arguments: d, r, α, θ and returns the DH matrix corresponding to these parameters for a single robot joint.

6 The Puma 560 Industrial Robot

The Unimation PUMA 560 is an industrial manipulator robot with 6 degrees of freedom and all rotational joints (i.e. it is a 6R mechanism).

It is shown in Figures 2 and 3.

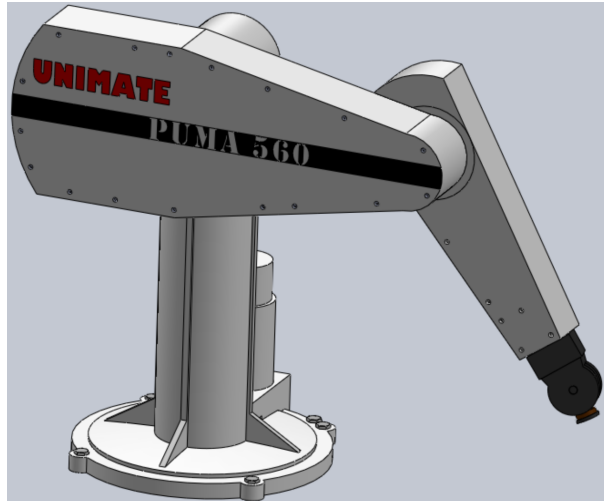


Figure 2: The Puma 560 Industrial Robot.

The DH table for its joints is:

Joint	θ	r	d	α
1	θ_1	0	0	0
2	θ_2	0	0	-90°
3	θ_3	r_2	d_3	0
4	θ_4	r_3	d_4	-90°
5	θ_5	0	0	90°
6	θ_6	0	0	-90°

Use the implemented Matlab function of the previous Exercise 5, calculate the position of the Puma 560 tool (end-effector).

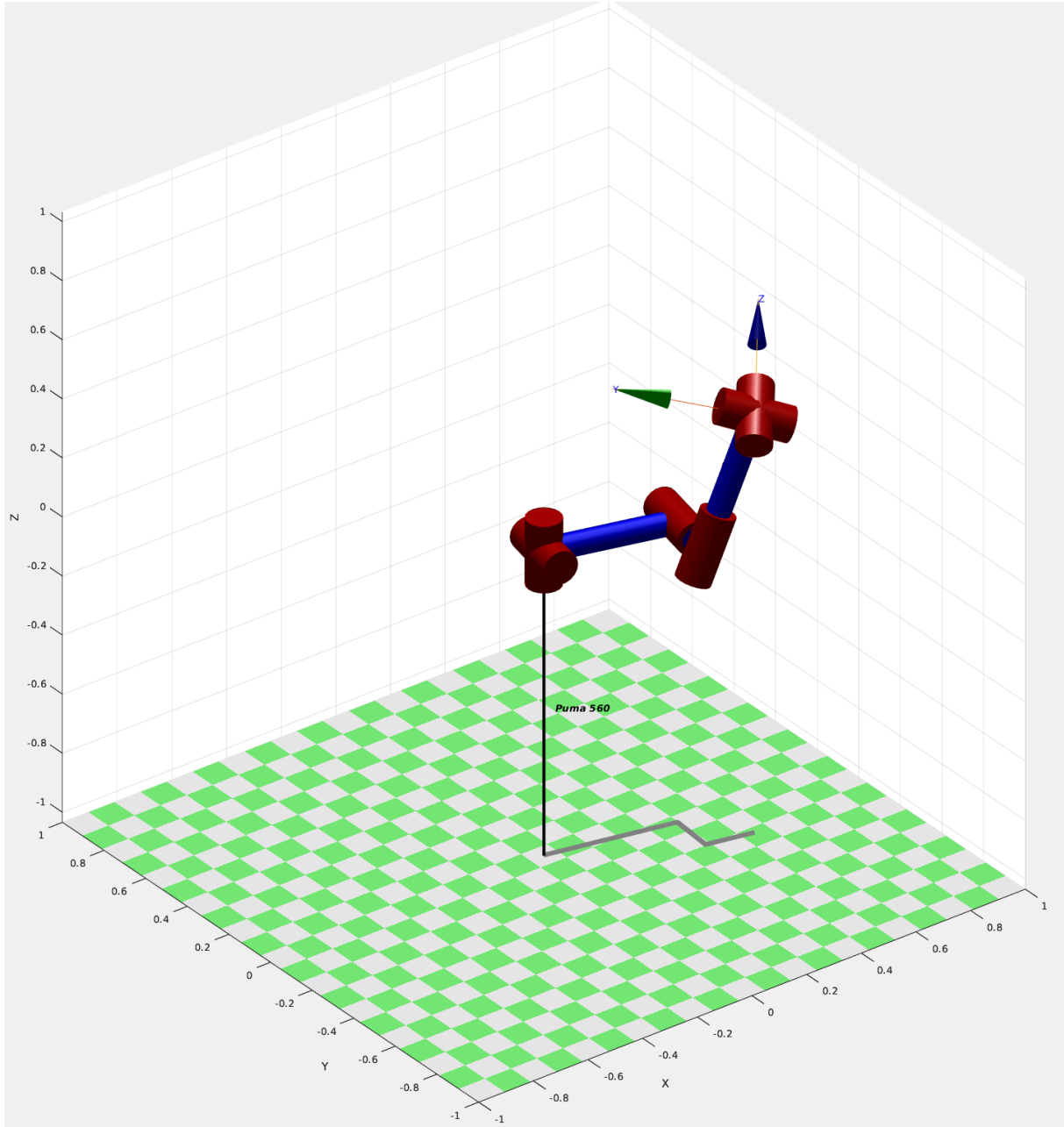


Figure 3: The Puma 560 Robot model in Matlab (Peter Corke's toolbox).