

# Appendix

## Implementation and Proofs

### A.1 Computing the Partial Derivatives of the Inertia Matrix

To compute the Coriolis matrix we need the partial derivatives of the terms in the inertia matrix which are found by the partial derivatives of the Adjoint and Jacobian matrices. The partial derivatives of the inertia matrix  $M(q_1, \dots, q_n)$  with respect to  $q_1, \dots, q_n$  are computed by

$$\begin{aligned} & \frac{\partial M(q_1, \dots, q_n)}{\partial q_k} \\ &= \sum_{i=k}^n \left( \begin{bmatrix} H^T \\ J_i^T \end{bmatrix} \left[ \frac{\partial^T \text{Ad}_{g_{ib}}}{\partial q_k} I_i \text{Ad}_{g_{ib}} + \text{Ad}_{g_{ib}}^T I_i \frac{\partial \text{Ad}_{g_{ib}}}{\partial q_k} \right] \begin{bmatrix} H & J_i \end{bmatrix} \right) \\ &+ \sum_{i=k+1}^n \begin{bmatrix} 0 & H^T \text{Ad}_{g_{ib}}^T I_i \text{Ad}_{g_{ib}} \frac{\partial J_i}{\partial q_k} \\ \frac{\partial^T J_i}{\partial q_k} \text{Ad}_{g_{ib}}^T I_i \text{Ad}_{g_{ib}} H & \frac{\partial^T J_i}{\partial q_k} \text{Ad}_{g_{ib}}^T I_i \text{Ad}_{g_{ib}} J_i + J_i^T \text{Ad}_{g_{ib}}^T I_i \text{Ad}_{g_{ib}} \frac{\partial J_i}{\partial q_k} \end{bmatrix}. \end{aligned} \tag{A.1}$$

The Coriolis matrix is thus found by the partial derivatives of the Adjoint and Jacobian matrices with respect to each joint variable  $q_k$ .

#### A.1.1 Computing the Partial Derivatives of $\text{Ad}_{g_{ij}}$

The main computational burden when computing the Coriolis matrix is on the computation of the partial derivatives of  $M$  with respect to  $q$  for which we need the partial derivatives of the Adjoint matrices, also with respect to  $q$ . To compute these one can use a relatively simple relation. If we express the velocity of joint  $k$  as  $V_{(k-1)k}^{(k-1)} = X_k^k \dot{q}_k$  for constant  $X_k^k$ , then the following holds (From et al. 2010):

**Proposition A.1** *The partial derivatives of the Adjoint matrix is given by*

$$\frac{\partial \text{Ad}_{g_{ij}}}{\partial q_k} = \begin{cases} \text{Ad}_{g_{i(k-1)}} \text{ad}_{X_k^k} \text{Ad}_{g_{(k-1)j}} & \text{for } i < k \leq j \\ -\text{Ad}_{g_{i(k-1)}} \text{ad}_{X_k^k} \text{Ad}_{g_{(k-1)j}} & \text{for } j < k \leq i \\ 0 & \text{otherwise} \end{cases}$$

*Proof (By computing the spatial velocity)* To prove this, we start by writing out the spatial velocity of frame  $\mathcal{F}_k$  with respect to  $\mathcal{F}_{(k-1)}$  when  $i < k \leq j$ :

$$\hat{X}_k \dot{q}_k = \hat{V}_{(k-1)k}^{(k-1)} = \dot{g}_{(k-1)k} g_{(k-1)k}^{-1} = \frac{\partial g_{(k-1)k}}{\partial q_k} g_{(k-1)k} \dot{q}_k$$

where  $\hat{X} = \begin{bmatrix} \hat{X}_\omega & X_v \\ 0 & 0 \end{bmatrix}$ . If we compare the first and the last terms, we get

$$\frac{\partial R_{(k-1)k}}{\partial q_k} = \hat{X}_\omega R_{(k-1)k}, \quad (\text{A.2})$$

$$\frac{\partial P_{(k-1)k}}{\partial q_k} = \hat{X}_\omega P_{(k-1)k} + X_v. \quad (\text{A.3})$$

We can use this relation in the expression for the partial derivative of  $\text{Ad}_{g_{(k-1)k}}$ :

$$\begin{aligned} \frac{\partial \text{Ad}_{g_{(k-1)k}}}{\partial q_k} &= \begin{bmatrix} \frac{\partial R_{(k-1)k}}{\partial q_k} & \hat{P}_{(k-1)k} R_{(k-1)k} + \hat{P}_{(k-1)k} \frac{\partial R_{(k-1)k}}{\partial q_k} \\ 0 & \frac{\partial R_{(k-1)k}}{\partial q_k} \end{bmatrix} \\ &= \begin{bmatrix} \hat{X}_\omega R_{(k-1)k} & \widehat{\hat{X}_\omega P_{(k-1)k} R_{(k-1)k} + \hat{X}_v R_{(k-1)k} + \hat{P}_{(k-1)k} \hat{X}_\omega R_{(k-1)k}} \\ 0 & \hat{X}_\omega R_{(k-1)k} \end{bmatrix} \\ &= \begin{bmatrix} \hat{X}_\omega R_{(k-1)k} & \hat{X}_\omega \hat{P}_{(k-1)k} R_{(k-1)k} + \hat{X}_v R_{(k-1)k} \\ 0 & \hat{X}_\omega R_{(k-1)k} \end{bmatrix} \\ &= \begin{bmatrix} \hat{X}_\omega & \hat{X}_v \\ 0 & \hat{X}_\omega \end{bmatrix} \begin{bmatrix} R_{(k-1)k} & \hat{P}_{(k-1)k} R_{(k-1)k} \\ 0 & R_{(k-1)k} \end{bmatrix} \\ &= \text{ad}_{X_k^k} \text{Ad}_{g_{(k-1)k}} \end{aligned} \quad (\text{A.4})$$

where we have used that

$$\hat{X} \hat{p} = \widehat{(\hat{X} p)} + \hat{p} \hat{X}. \quad (\text{A.5})$$

It is now straight forward to show that

$$\begin{aligned} \frac{\partial \text{Ad}_{g_{ij}}}{\partial q_k} &= \text{Ad}_{g_{i(k-1)}} \frac{\partial \text{Ad}_{g_{(k-1)k}}}{\partial q_k} \text{Ad}_{g_{kj}} \\ &= \text{Ad}_{g_{i(k-1)}} \text{ad}_{X_k^k} \text{Ad}_{g_{(k-1)k}} \text{Ad}_{g_{kj}} \\ &= \text{Ad}_{g_{i(k-1)}} \text{ad}_{X_k^k} \text{Ad}_{g_{(k-1)j}}. \end{aligned} \quad (\text{A.6})$$

The proof is similar for  $j < k \leq i$ .  $\square$

*Proof (By direct computation)* We can also prove Proposition A.1 by direct computation. For  $i < k \leq j$  the proof is shown by

$$\begin{aligned}
& \frac{\partial \text{Ad}_{g_{ij}}}{\partial q_k} \\
&= \text{Ad}_{g_{i(k-1)}} \frac{\partial \text{Ad}_{g^{(k-1)k}}}{\partial q_k} \text{Ad}_{g_{kj}} \\
&= \begin{bmatrix} R_{i(k-1)} & \hat{p}_{i(k-1)} R_{i(k-1)} \\ 0 & R_{i(k-1)} \end{bmatrix} \begin{bmatrix} \frac{\partial R_{(k-1)k}}{\partial q_k} & \frac{\hat{p}_{(k-1)k}}{\partial q_k} R_{(k-1)k} + \hat{p}_{(k-1)k} \frac{\partial R_{(k-1)k}}{\partial q_k} \\ 0 & \frac{\partial R_{(k-1)k}}{\partial q_k} \end{bmatrix} \\
&\quad \times \begin{bmatrix} R_{kj} & \hat{p}_{kj} R_{kj} \\ 0 & R_{kj} \end{bmatrix} \\
&= \begin{bmatrix} R_{i(k-1)} \frac{\partial R_{(k-1)k}}{\partial q_k} R_{kj} & \begin{bmatrix} R_{i(k-1)} \frac{\partial R_{(k-1)k}}{\partial q_k} \hat{p}_{kj} R_{kj} \\ + R_{i(k-1)} \frac{\hat{p}_{(k-1)k}}{\partial q_k} R_{(k-1)j} \\ + R_{i(k-1)} \hat{p}_{(k-1)k} \frac{\partial R_{(k-1)k}}{\partial q_k} R_{kj} \\ + \hat{p}_{i(k-1)} R_{i(k-1)} \frac{\partial R_{(k-1)k}}{\partial q_k} R_{kj} \end{bmatrix} \\ 0 & R_{i(k-1)} \frac{\partial R_{(k-1)k}}{\partial q_k} R_{kj} \end{bmatrix} \\
&= \begin{bmatrix} R_{i(k-1)} \hat{X}_\omega R_{(k-1)k} R_{kj} & \begin{bmatrix} R_{i(k-1)} \hat{X}_\omega R_{(k-1)k} \hat{p}_{kj} R_{kj} \\ + R_{i(k-1)} ((\hat{X}_\omega P_{(k-1)k}) + \hat{X}_v) R_{(k-1)j} \\ + R_{i(k-1)} \hat{p}_{(k-1)k} \hat{X}_\omega R_{(k-1)k} R_{kj} \\ + \hat{p}_{i(k-1)} R_{i(k-1)} \hat{X}_\omega R_{(k-1)k} R_{kj} \\ R_{i(k-1)} \hat{X}_\omega R_{(k-1)k} R_{kj} \end{bmatrix} \\ 0 & R_{i(k-1)} \hat{X}_\omega R_{(k-1)k} R_{kj} \end{bmatrix} \\
&= \begin{bmatrix} R_{i(k-1)} \hat{X}_\omega R_{(k-1)j} & \begin{bmatrix} R_{i(k-1)} \hat{X}_v R_{(k-1)j} + R_{i(k-1)} \hat{X}_\omega \hat{p}_{(k-1)j} R_{(k-1)j} \\ + \hat{p}_{i(k-1)} R_{i(k-1)} \hat{X}_\omega R_{(k-1)j} \end{bmatrix} \\ 0 & R_{i(k-1)} \hat{X}_\omega R_{(k-1)j} \end{bmatrix} \\
&= \begin{bmatrix} R_{i(k-1)} \hat{X}_\omega & R_{i(k-1)} \hat{X}_v + \hat{p}_{i(k-1)} R_{i(k-1)} \hat{X}_\omega \\ 0 & R_{i(k-1)} \hat{X}_\omega \end{bmatrix} \begin{bmatrix} R_{(k-1)j} & \hat{p}_{(k-1)j} R_{(k-1)j} \\ 0 & R_{(k-1)j} \end{bmatrix} \\
&= \begin{bmatrix} R_{i(k-1)} & \hat{p}_{i(k-1)} R_{i(k-1)} \\ 0 & R_{i(k-1)} \end{bmatrix} \begin{bmatrix} \hat{X}_\omega & \hat{X}_v \\ 0 & \hat{X}_\omega \end{bmatrix} \begin{bmatrix} R_{(k-1)j} & \hat{p}_{(k-1)j} R_{(k-1)j} \\ 0 & R_{(k-1)j} \end{bmatrix} \\
&= \text{Ad}_{g_{i(k-1)}} \text{ad}_{X_k^k} \text{Ad}_{g^{(k-1)j}} \tag{A.7}
\end{aligned}$$

where we have used Eq. (A.5) and

$$\hat{p}_{(k-1)j} = (\widehat{R_{(k-1)k} P_{kj}}) + \hat{p}_{(k-1)k}. \tag{A.8}$$

$\square$

### A.1.2 Computing the Jacobian and Its Partial Derivatives

The Jacobian  $\bar{J}_i$  of link  $i$  is given by

$$J_i(q) = [\text{Ad}_{g_{0\bar{1}}} X_1^1 \quad \text{Ad}_{g_{0\bar{2}}} X_2^2 \quad \text{Ad}_{g_{0\bar{3}}} X_3^3 \quad \cdots \quad \text{Ad}_{g_{0\bar{i}}} X_i^i \quad 0_{(n-i) \times 6}]. \quad (\text{A.9})$$

When the partial derivatives of the Adjoint map are found as in the previous section we can also use these to find the partial derivatives of the Jacobian, i.e.,

$$\frac{\partial J_i}{\partial q_k} = \begin{bmatrix} 0_{(k-1) \times 6} & \frac{\partial \text{Ad}_{g_{b\bar{k}}}}{\partial q_k} X_k^k & \frac{\partial \text{Ad}_{g_{b(\bar{k}+1)}}}{\partial q_k} X_{k+1}^{k+1} & \cdots & \frac{\partial \text{Ad}_{g_{b\bar{i}}}}{\partial q_k} X_i^i & 0_{(n-i) \times 6} \end{bmatrix}. \quad (\text{A.10})$$

### A.1.3 Implementation

In this section we will show how to compute the Coriolis matrix for implementation purposes. We will show this for  $SO(3)$  for which the Coriolis matrix is given by

$$C(Q, v) = \sum_{k=1}^n \frac{\partial M}{\partial q_k} \dot{q}_k - \frac{1}{2} \begin{bmatrix} \widehat{(M(q)v)}_{\tilde{v}} & 0 \\ \frac{\partial^\top}{\partial q} \left( [M_{VV} \quad M_{qV}^\top] \begin{bmatrix} \tilde{V}_{0b}^B \\ \dot{q} \end{bmatrix} \right) & \frac{\partial^\top}{\partial q} \left( [M_{qV} \quad M_{qq}^\top] \begin{bmatrix} \tilde{V}_{0b}^B \\ \dot{q} \end{bmatrix} \right) \end{bmatrix} \quad (\text{A.11})$$

where  $(M(q)v)_{\tilde{v}}$  is the vector of the first three entries of the vector  $M(q)v$  (corresponding to  $\tilde{V}_{0b}^B = \omega_{0b}^B$ ).

We first define the vector

$$(M(q)v)_{\tilde{v}} = \begin{bmatrix} (M(q)v)_1 \\ (M(q)v)_2 \\ (M(q)v)_3 \end{bmatrix} = \begin{bmatrix} M_{VV} & M_{qV}^\top \end{bmatrix} \begin{bmatrix} V_{0b}^B \\ \dot{q} \end{bmatrix} \quad (\text{A.12})$$

which gives

$$\text{ad}_{(M(q)v)_{\tilde{v}}} = \begin{bmatrix} 0 & -(M(q)v)_3 & (M(q)v)_2 \\ (M(q)v)_3 & 0 & -(M(q)v)_1 \\ -(M(q)v)_2 & (M(q)v)_1 & 0 \end{bmatrix}. \quad (\text{A.13})$$

The lower part of the second part of (A.11) is calculated as

$$\begin{aligned}
 & \frac{\partial^T}{\partial q} \left( [M_{VV} \ M_{qV}^T] \begin{bmatrix} V_{0b}^B \\ \dot{q} \end{bmatrix} \right) \\
 &= \begin{bmatrix} \frac{\partial(Mv)_1}{\partial q_1} & \frac{\partial(Mv)_2}{\partial q_1} & \frac{\partial(Mv)_3}{\partial q_1} \\ \frac{\partial(Mv)_1}{\partial q_2} & \frac{\partial(Mv)_2}{\partial q_2} & \frac{\partial(Mv)_3}{\partial q_2} \\ \vdots & \vdots & \vdots \\ \frac{\partial(Mv)_1}{\partial q_n} & \frac{\partial(Mv)_2}{\partial q_n} & \frac{\partial(Mv)_3}{\partial q_n} \end{bmatrix} \\
 &= \begin{bmatrix} \sum_{i=1}^{3+n} \frac{\partial M_{1i}}{\partial q_1} v_i & \sum_{i=1}^{3+n} \frac{\partial M_{2i}}{\partial q_1} v_i & \sum_{i=1}^{3+n} \frac{\partial M_{3i}}{\partial q_1} v_i \\ \sum_{i=1}^{3+n} \frac{\partial M_{1i}}{\partial q_2} v_i & \sum_{i=1}^{3+n} \frac{\partial M_{2i}}{\partial q_2} v_i & \sum_{i=1}^{3+n} \frac{\partial M_{3i}}{\partial q_2} v_i \\ \vdots & \vdots & \vdots \\ \sum_{i=1}^{3+n} \frac{\partial M_{1i}}{\partial q_n} v_i & \sum_{i=1}^{3+n} \frac{\partial M_{2i}}{\partial q_n} v_i & \sum_{i=1}^{3+n} \frac{\partial M_{3i}}{\partial q_n} v_i \end{bmatrix} \tag{A.14}
 \end{aligned}$$

$$\begin{aligned}
 \frac{\partial^T}{\partial q} \left( [M_{qV} \ M_{qq}^T] \begin{bmatrix} V_{0b}^B \\ \dot{q} \end{bmatrix} \right) &= \begin{bmatrix} \sum_{i=1}^{3+n} \frac{\partial M_{(m+1)i}}{\partial q_1} v_i & \cdots & \sum_{i=1}^{3+n} \frac{\partial M_{(m+n)i}}{\partial q_1} v_i \\ \sum_{i=1}^{3+n} \frac{\partial M_{(m+1)i}}{\partial q_2} v_i & \cdots & \sum_{i=1}^{3+n} \frac{\partial M_{(m+n)i}}{\partial q_2} v_i \\ \vdots & \ddots & \vdots \\ \sum_{i=1}^{3+n} \frac{\partial M_{(m+1)i}}{\partial q_n} v_i & \cdots & \sum_{i=1}^{3+n} \frac{\partial M_{(m+n)i}}{\partial q_n} v_i \end{bmatrix} \tag{A.15}
 \end{aligned}$$

and is thus also given by the partial derivative of the elements of the inertia matrix. We thus only need to compute the partial derivative  $\frac{\partial M(q)}{\partial q_i}$  once and use the result in the both in the first and second part of (A.11). This will simplify the computation of the dynamic equations for an arbitrary  $n$ -link mechanism mounted on a vehicle.

### References

From, P. J., Duindam, V., Pettersen, K. Y., Gravdahl, J. T., and Sastry, S. (2010). Singularity-free dynamic equations of vehicle-manipulator systems. *Simulation Modelling Practice and Theory*, 18(6), 712–731.

# Index

## Symbols

1-parameter motion, 135

## A

Actions on Lie groups, 57  
Adjoint map Ad, 58, 114  
Adjoint map ad, 62  
Analytical Jacobian, 238  
  of a manipulator, 238  
Automation, 1  
Autonomous robots, 3  
Autonomous underwater vehicle, 307–323  
AUV-manipulator systems, 7, 307–323

## B

Basis elements, 64, 66  
Body velocity, 55, 92, 99, 101, 111, 112, 146, 171  
  of a vehicle-manipulator system, 175, 177, 249  
Boltzmann–Hamel equations, 201, 211  
  of a vehicle-manipulator system, 263  
Boundedness property, 285–304  
  definition, 288  
  weak, 293

## C

Cartesian basis, 20  
Center of mass, 338  
Charts, 82  
Christoffel symbols, 237, 297  
Circle, 32  
Complex number, 39  
Configuration space, 30, 113  
  special Euclidean group, 107  
Configuration state, 108, 164, 169, 181  
  matrix group, 108

  of a manipulator, 166, 240  
  of a vehicle-manipulator system, 169, 181, 266  
  prismatic joint, 165  
  revolute joint, 165  
  special Euclidean group, 109  
Configuration states, 260  
  underwater robots, 322  
Conjugation, 57  
Control, 290–292, 375–377  
Coordinate  
  exponential, 86  
  homogeneous, 52  
  local, 46, 85, 120, 167, 181, 213, 244  
  of a manipulator, 244  
Coordinate chart, 31, 35  
Coordinate system, 19  
Coriolis matrix, 204, 216, 225, 236, 285–304  
  Euclidean group, 277  
  local coordinates, 216, 244  
  of a manipulator, 236, 244  
  of a vehicle-manipulator system, 251, 256, 258, 259, 265, 268, 275–278  
  operational space, 238  
  planar group, 222  
  properties, 285–304  
  representation, 204  
  Schönflies group, 224  
  skew symmetry, 204, 285–304  
  special Euclidean group, 221, 276  
  special orthogonal group, 219, 275  
Cranes, 370

## D

D'Alembert's principle, 191  
Degree of freedom, 360  
Dependent variables, 341

Differentiable degree of freedom, 360  
 Dynamically equivalent manipulator, 7, 348

**E**

Euclidean space, 39  
 Euclidean transformation, 22, 24  
 Euler angles, 94, 100  
 Euler–Lagrange equations, 192, 193, 197, 203, 209  
   definition, 198  
 Euler–Poincaré equations, 201, 207  
 Euler’s equations, 200  
 Exponential map, 73, 76, 78, 82, 133, 138, 218  
   of a matrix, 74

**F**

Field robots, 8, 355–368, 371–373  
   configuration spaces, 359  
   degree of freedom, 360  
   differentiable degree of freedom, 360  
   kinematics, 362, 366  
   legged robots, 357  
   locomotion, 357  
   mobility, 359  
   non-holonomic motion, 360  
   rolling constraint, 366  
   sliding constraint, 367  
   wheel kinematics, 366  
   wheeled robots, 357, 362  
 Flow, 71, 76  
 Forced base motion, 8, 369–377  
 Forward kinematics, 131, 133, 138

**G**

Generalized coordinates, 22, 191, 207, 252  
 Generalized inertia matrix, 195, 230  
 Generalized velocities, 23, 207  
 Geometric integrator, 88  
 Gibbs–Appel equations, 225  
 Gravitational field, 197  
 Gravitational forces, 197, 237, 315  
   vehicle-manipulator system, 256  
 Group, 37  
   general linear, 41  
   orthogonal, 42  
   planar, 45  
   Schönflies, 44, 45  
   special Euclidean, 43, 45  
   special orthogonal, 42, 45  
   subgroup, 45  
   translational, 45

**H**

Hamilton’s extended principle, 200

Hausdorff space, 29  
 Home position, 126, 133  
 Homeomorphism, 29  
 Homogeneous transformation, 129

**I**

Independent variables, 341  
 Inertia matrix, 195, 218, 285–304  
   boundedness, 285–304  
   configuration dependent, 202, 218, 230, 249, 258, 294  
   of a manipulator, 230  
   of a vehicle-manipulator system, 249, 251, 256, 258, 259, 265  
   operational space, 238  
   properties, 271, 285–304  
 Integral curve, 69, 71  
 Isomorphism, 29

**J**

Jacobian, 103, 105, 172, 259  
   analytical, 150, 163  
   body geometric, 149, 150, 152, 173, 176, 178, 179  
   body geometric link, 162  
   constraint, 340  
   end effector, 178  
   Generalized Jacobian Matrix, 341  
   link, 173  
   of a manipulator, 149  
   of a vehicle-manipulator system, 173, 176, 178  
   spatial geometric, 149, 156, 157, 173, 176, 178  
   spatial geometric link, 161  
   workspace, 179, 259

**Joint**

prismatic, 130, 136  
 revolute, 130, 136

**K**

Kane’s equations, 192  
 Kinematic energy, 192  
 Kinematics, 126  
   static, 126  
 Kinetic energy, 194, 195  
 Kirchhoff’s equations, 202

**L**

Lagrangian, 192–194  
   definition, 198  
   local coordinates, 267  
   partial derivative, 207, 208, 215, 242, 261, 262, 267  
 Left multiplication, 58

- Lie algebra, 46
- Lie bracket, 47, 62
- Lie group, 36, 50
  - actions, 57
  - definition, 38
  - Euclidean, 47, 79, 86
  - Euclidean space, 64
  - general linear, 47, 82
  - interpretation, 50
  - matrix, 41, 46, 51, 84
  - planar, 49, 61, 67, 81, 116
  - representation, 51
  - Schönflies, 50, 67, 118
  - special Euclidean, 49, 60, 66, 80, 88, 104, 109
  - special orthogonal, 48, 59, 79, 87, 93, 116
  - subgroup, 45
  - translational, 91, 115
- Link transformation
  - configuration dependent, 129
  - configuration independent, 129
- Local coordinates, 266
- Locomotion, 357
  - fixed wheels, 366
  - steered wheels, 366
- M**
- Manifold, 27, 30, 31, 35, 46, 69
- Manipulator twist, 135
- Matrix form, 199
- Mobile robots, 2
  - classification, 5
- Mobility, 359
- Momentum, 200
  - angular, 200, 338
  - body, 200
  - conservation, 200, 338
  - linear, 338
  - spatial, 200
- Motion planning, 376, 377
- Moving base, 369
- N**
- Newton–Euler equations, 192
- Newton’s laws, 193, 197, 335
- Non-Euclidean transformation, 22, 24
- Non-holonomic motion, 341, 360
  - definition, 364
  - space robots, 341
- Non-inertial forces, 369–377
- Non-inertial motion, 369–377
- Norm, 288
  - induced, 288
- O**
- Operational space, 238, 259, 321
- P**
- Planar motion, 44
- Positive definiteness
  - definition, 290
- Potential energy, 192
- Potential field, 197, 198
- Potential forces, 197
- Principle of conservation of energy, 287
- Product of exponentials formula, 133, 138
  - theorem, 135
- Q**
- Quasi-coordinates, 25, 100, 193, 207
- Quasi-velocities, 23, 25, 207, 248, 252
- Quaternion, 40, 97
- R**
- Redundancy, 341
  - global, 341
  - local, 341
  - non-holonomic, 341
- Reference frame, 17, 126
  - center of gravity  $\mathcal{F}_i$ , 127
  - end-effector frame  $\mathcal{F}_e$ , 129
  - inertial, 17, 126, 335
  - link frame  $\tilde{\mathcal{F}}_i$ , 127
  - link frame  $\mathcal{F}_i$ , 126
  - non-inertial, 18, 126, 335
- Remotely operated vehicle, 307–323
- Right multiplication, 58
- Robot on a moving base, 377
- Rolling constraint, 366
- Rotation matrix, 94, 95
  - definition, 97
  - properties, 97
- S**
- Seaborne platforms, 370
- Selection matrix, 108
  - definition, 114
  - special orthogonal group, 219
- Service robots, 9
- Singularity, 106
- Skew symmetry, 48
- Skew-symmetric property, 285–304
  - definition, 289
- Sliding constraint, 367
- Space robots, 7, 325–353, 357
  - actuation, 333
  - angular momentum, 338
  - conservation of angular momentum, 333
  - control, 344, 348



- Space robots (*cont.*)
  - coordinate frames, 335
  - decoupled motion, 345
  - dependent variables, 341
  - disturbances, 332
  - dynamic singularities, 343
  - dynamically equivalent manipulator, 348
  - dynamics, 336
  - fast attitude control, 333
  - free-floating robots, 347
  - free-flying robots, 343
  - Generalized Jacobian Matrix, 341
  - gravity field, 332
  - independent variables, 341
  - Jacobian, 340
  - kinematics, 336, 337
  - linear momentum, 338
  - magnetic field, 332
  - non-holonomic motion, 341
  - redundancy, 341
  - slow attitude control, 333
  - solar radiation, 332
  - state space, 345
  - thrusters, 333
  - virtual manipulator, 348
- Spacecraft-manipulator systems, 7
- Spatial velocity, 54, 93, 98, 101, 111, 112, 146, 162, 171
  - of a vehicle-manipulator system, 175, 177
  - of frame  $\mathcal{F}_i$ , 128
  - of frame  $\mathcal{F}_i$ , 128
- Sphere, 34, 46
- State space
  - of a manipulator, 240
  - of a vehicle-manipulator system, 248
- Subgroup, 113
- T**
- Tangent bundle, 70
- Tangent space, 69
- Teleoperation, 3
- Topological space, 28
- Topology, 27
- Twist, 100, 135
  - body, 138
  - body joint, 136, 137
  - joint, 151, 157
  - spatial, 136–138
- U**
- Underwater manipulator arms, 312
- Underwater robots, 7, 307–323
  - actuation, 316
  - actuation matrix, 316
  - added mass, 313, 314
  - azimuth thrusters, 316
  - buoyancy forces, 315
  - disturbances, 318
  - dynamics, 313
  - gravitational forces, 315
  - operational space, 321
  - potential damping, 313, 315
  - propellers, 316
  - restoring forces, 313
  - rudders, 316
  - tunnel thrusters, 316
  - vehicle-manipulator systems, 320
- V**
- Variation, 200
- Vector field, 69, 71
- Vector space, 46
- Vee map, 104
- Velocity
  - end effector, 146
  - inertial, 146
  - link, 173
- Velocity transformation matrix, 85, 86, 103, 105, 172
- Velocity transformation matrix  $S$ , 120, 181, 209, 213, 225
  - planar group, 122
  - properties, 271
  - Schönflies group, 123
  - special Euclidean group, 121
  - special orthogonal group, 122
- Virtual work, 191, 201
- W**
- Work, 257, 258, 263