ECE276A: Sensing & Estimation in Robotics
Lecture 6: Rotations

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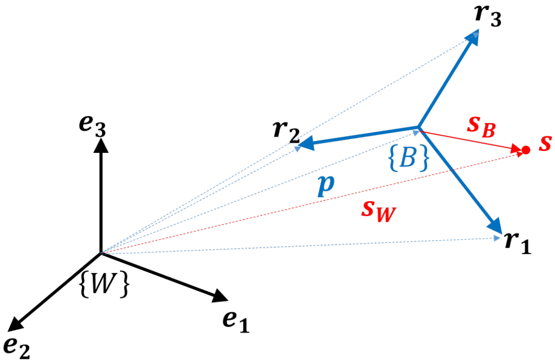
Rigid Body Motion

- Consider a moving object in a fixed **world reference frame** $\{W\}$
- **Rigid object**: it is sufficient to specify the motion of one point $\mathbf{p}(t) \in \mathbb{R}^3$ and 3 coordinate axes $\mathbf{r}_1(t)$, $\mathbf{r}_2(t)$, $\mathbf{r}_3(t)$ attached to that point (**body reference frame** $\{B\}$)
- A point $\mathbf{s}$ on the rigid body has fixed coordinates $\mathbf{s}_B \in \mathbb{R}^3$ in the body frame but time-varying coordinates $\mathbf{s}_W(t) \in \mathbb{R}^3$ in the world frame.



Rigid Body Motion

- A rigid body is free to translate (3 degrees of freedom) and rotate (3 degrees of freedom)

- The **pose** $T(t) \in SE(3)$ of a moving rigid object $\{B\}$ at time t in a fixed world frame $\{W\}$ is determined by
  1. The position $\mathbf{p}(t) \in \mathbb{R}^3$ of $\{B\}$ relative to $\{W\}$
  2. The orientation $R(t) \in SO(3)$ of $\{B\}$ relative to $\{W\}$

- The space $\mathbb{R}^3$ of positions is familiar

- How do we describe the space $SO(3)$ of orientations and the space $SE(3)$ of poses?

Special Euclidean Group

- **Rigid body motion** is a family of transformations $g(t) : \mathbb{R}^3 \to \mathbb{R}^3$ that describe how the coordinates of points on the object change in time
- Rigid body motion preserves distances (vector norms) and does not allow reflection of the coordinate system (vector cross products)
- **Euclidean Group** $E(3)$: a set of maps $g : \mathbb{R}^3 \to \mathbb{R}^3$ that preserve the norm of any two vectors
- **Special Euclidean Group** $SE(3)$: a set of maps $g : \mathbb{R}^3 \to \mathbb{R}^3$ that preserve the norm and cross product of any two vectors
- The set of rigid body motions forms a group because:
  - We can combine several motions to generate a new one (**closure**)
  - We can execute a motion that leaves the object at the same state (**identity element**)
  - We can move rigid objects from one place to another and then reverse the action (**inverse element**)

Special Euclidean Group

- A **group** is a set G with an associated operator $\odot$ (group law of G) that satisfies:
  - **Closure**: $a \odot b \in G, \forall a, b \in G$
  - **Identity element**: $\exists! e \in G$ (unique) such that $e \odot a = a \odot e = a$
  - **Inverse element**: for $a \in G$, $\exists b \in G$ such that $a \odot b = b \odot a = e$
  - **Associativity**: $(a \odot b) \odot c = a \odot (b \odot c), \forall a, b, c, \in G$

- $SE(3)$ is a group of maps $g : \mathbb{R}^3 \to \mathbb{R}^3$ that preserve:
  1. Norm: $\|g(\mathbf{u}) - g(\mathbf{v})\| = \|\mathbf{v} - \mathbf{u}\|, \forall \mathbf{u}, \mathbf{v} \in \mathbb{R}^3$
  2. Cross product: $g(\mathbf{u}) \times g(\mathbf{v}) = g(\mathbf{u} \times \mathbf{v}), \forall \mathbf{u}, \mathbf{v} \in \mathbb{R}^3$

- **Corollary**: $SE(3)$ elements also preserve:
  1. Angle: $\mathbf{u}^\top \mathbf{v} = \frac{1}{4}\left(\|\mathbf{u} + \mathbf{v}\|^2 - \|\mathbf{u} - \mathbf{v}\|^2\right) \Rightarrow \mathbf{u}^\top \mathbf{v} = g(\mathbf{u})^\top g(\mathbf{v}), \forall \mathbf{u}, \mathbf{v} \in \mathbb{R}^3$
  2. Volume: $\forall \mathbf{u}, \mathbf{v}, \mathbf{w} \in \mathbb{R}^3$, $g(\mathbf{u})^\top (g(\mathbf{v}) \times g(\mathbf{w})) = \mathbf{u}^\top (\mathbf{v} \times \mathbf{w})$
     (volume of parallelepiped spanned by $\mathbf{u}, \mathbf{v}, \mathbf{w}$)

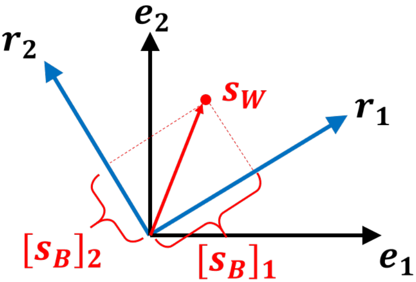
Orientation and Rotation

- Pure rotational motion is a special case of rigid body motion
- First, we need to define the orientation of a rigid body
- The orientation of a body frame $\{B\}$ is determined by the coordinates of the three orthogonal vectors $\mathbf{r}_1 = g(\mathbf{e}_1)$, $\mathbf{r}_2 = g(\mathbf{e}_2)$, $\mathbf{r}_3 = g(\mathbf{e}_3)$ in the world frame $\{W\}$, i.e., by the 3×3 matrix:

$$R = \begin{bmatrix} \mathbf{r}_1 & \mathbf{r}_2 & \mathbf{r}_3 \end{bmatrix} \in \mathbb{R}^{3\times 3}$$

- Consider a point with coordinates $\mathbf{s}_B \in \mathbb{R}^3$ in $\{B\}$
- Its coordinates $\mathbf{s}_W$ in $\{W\}$ are:

$$\begin{aligned} \mathbf{s}_W &= [s_B]_1 \mathbf{r}_1 + [s_B]_2 \mathbf{r}_2 + [s_B]_3 \mathbf{r}_3 \\ &= R\mathbf{s}_B \end{aligned}$$



Special Orthogonal Group $SO(3)$

- $\mathbf{r}_1$, $\mathbf{r}_2$, $\mathbf{r}_3$ form an orthonormal basis: $\mathbf{r}_i^\top \mathbf{r}_j = \begin{cases} 1 & \text{if } i = j \\ 0 & \text{otherwise} \end{cases}$
- R belongs to the **orthogonal group**:

$$O(3) := \{R \in \mathbb{R}^{3\times 3} \mid R^\top R = RR^\top = I\}$$

- The inverse of R is its transpose: $R^{-1} = R^T$
- Distances are preserved under rotation:

$$\|R(\mathbf{x}-\mathbf{y})\|_2^2 = (\mathbf{x}-\mathbf{y})^\top R^\top R(\mathbf{x}-\mathbf{y}) = (\mathbf{x}-\mathbf{y})^\top(\mathbf{x}-\mathbf{y}) = \|\mathbf{x}-\mathbf{y}\|_2^2$$

- One more property is needed to prevent reflections, i.e., to maintain a right-handed coordinate system:

$$R(\mathbf{x}\times\mathbf{y}) = R\left(\mathbf{x}\times(R^\top R\mathbf{y})\right) = (R\,[\mathbf{x}]_\times\,R^\top)R\mathbf{y} = \frac{1}{\det(R)}(R\mathbf{x})\times(R\mathbf{y})$$

- Note that $\det(R) = \mathbf{r}_1^\top(\mathbf{r}_2\times\mathbf{r}_3) = 1$
- Thus, R belongs to the **special orthogonal group**:

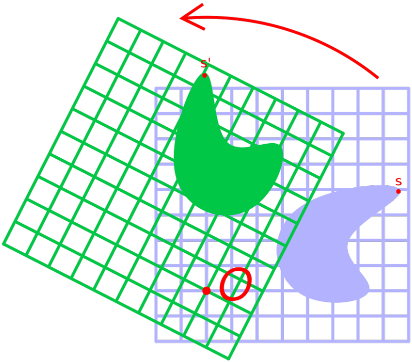
$$SO(3) := \{R \in \mathbb{R}^{3\times 3} \mid R^T R = I, \det(R) = 1\}$$

Parametrizing 2-D Rotations

- **Rotation angle**: a 2-D rotation of a point $\mathbf{s}_B \in \mathbb{R}^2$ can be parametrized by an angle θ:

$$\mathbf{s}_W = R(\theta)\mathbf{s}_B := \begin{bmatrix} \cos\theta & -\sin\theta \\ \sin\theta & \cos\theta \end{bmatrix} \mathbf{s}_B$$

- $\theta > 0$: counterclockwise rotation



- **Unit-norm complex number**: a 2-D rotation of $[s_B]_1 + i[s_B]_2 \in \mathbb{C}^2$ can be parametrized by a unit-norm complex number $e^{i\theta}$:

$$e^{i\theta}([s_B]_1 + i[s_B]_2) = ([s_B]_1 \cos\theta - [s_B]_2 \sin\theta) + i([s_B]_1 \sin\theta + [s_B]_2 \cos\theta)$$

Principal 3-D Rotations

- A rotation by an angle ϕ around the x-axis is represented by:

$$R_x(\phi) := \begin{bmatrix} 1 & 0 & 0 \\ 0 & \cos\phi & -\sin\phi \\ 0 & \sin\phi & \cos\phi \end{bmatrix}$$

- A rotation by an angle θ around the y-axis is represented by:

$$R_y(\theta) := \begin{bmatrix} \cos\theta & 0 & \sin\theta \\ 0 & 1 & 0 \\ -\sin\theta & 0 & \cos\theta \end{bmatrix}$$

- A rotation by an angle ψ around the z-axis is represented by:

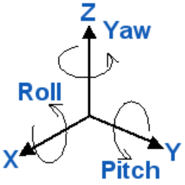
$$R_z(\psi) := \begin{bmatrix} \cos\psi & -\sin\psi & 0 \\ \sin\psi & \cos\psi & 0 \\ 0 & 0 & 1 \end{bmatrix}$$

Euler Angle Parametrization

- One way to parametrize rotation is to use three angles that specify the rotations around the principal axes
- There are 24 different ways to apply these rotations
  - **Extrinsic axes**: the rotation axes remain fixed/global/static
  - **Intrinsic axes**: the rotation axes move with the rotations
  - Each of the two groups (intrinsic and extrinsic) can be divided into:
    - **Euler Angles**: rotation about one axis, then a second and then the first
    - **Tait-Bryan Angles**: rotation about all three axes
  - The Euler and Tait-Bryan Angles each have 6 possible choices for each of the extrinsic/intrinsic groups leading to $2 * 2 * 6 = 24$ possible conventions to specify a rotation sequence with three given angles
- For simplicity we will refer to all these 24 conventions as **Euler Angles** and will explicitly specify:
  - r (rotating = intrinsic) or s (static = extrinic)
  - xyz or zyx or zxz, etc. (axes about which to perform the rotation in the specified order)

Common Euler Angle Conventions

- Spin (θ), nutation (γ), precession (ψ) sequence (*rzxz* convention):
  - A rotation ψ about the original *z*-axis
  - A rotation γ about the intermediate *x*-axis
  - A rotation θ about the transformed *z*-axis
- Roll (ϕ), pitch (θ), yaw (ψ) sequence (*rzyx* convention):
  - A rotation ϕ about the original *x*-axis
  - A rotation θ about the intermediate *y*-axis
  - A rotation ψ about the transformed *z*-axis



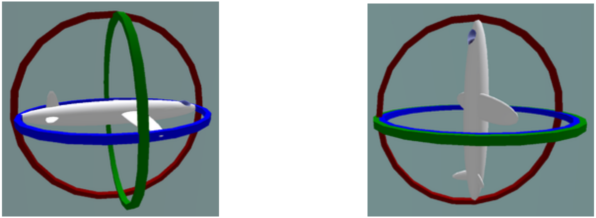
- We will call **Euler Angles** the **roll** (ϕ), **pitch** (θ), **yaw** (ψ) angles specifying an **XYZ extrinsic** or equivalently a **ZYX intrinsic** rotation:

$$R = R_z(\psi)R_y(\theta)R_x(\phi)$$

$$= \begin{bmatrix} \cos\psi & -\sin\psi & 0 \\ \sin\psi & \cos\psi & 0 \\ 0 & 0 & 1 \end{bmatrix} \begin{bmatrix} \cos\theta & 0 & \sin\theta \\ 0 & 1 & 0 \\ -\sin\theta & 0 & \cos\theta \end{bmatrix} \begin{bmatrix} 1 & 0 & 0 \\ 0 & \cos\phi & -\sin\phi \\ 0 & \sin\phi & \cos\phi \end{bmatrix}$$

Gimbal Lock

- Angle parametrizations are widely used due to their simplicity
- Unfortunately, in 3-D angle parametrizations have **singularities** (not one-to-one), which can result in **gimbal lock**, e.g., if the pitch becomes $\theta = 90^\circ$, the roll and yaw become associated with the same degree of freedom and cannot be uniquely determined.
- Gimbal lock is a problem only if we want to recover the rotation angles from a rotation matrix



Cross Product and Hat Map

- The **cross product** of two vectors $\mathbf{x}, \mathbf{y} \in \mathbb{R}^3$ is also a vector in $\mathbb{R}^3$:

$$\mathbf{x} \times \mathbf{y} := \begin{bmatrix} x_2 y_3 - x_3 y_2 \\ x_3 y_1 - x_1 y_3 \\ x_1 y_2 - x_2 y_1 \end{bmatrix} = \begin{bmatrix} 0 & -x_3 & x_2 \\ x_3 & 0 & -x_1 \\ -x_2 & x_1 & 0 \end{bmatrix} \begin{bmatrix} y_1 \\ y_2 \\ y_3 \end{bmatrix} = [\mathbf{x}]_\times \mathbf{y}$$

- The cross product $\mathbf{x} \times \mathbf{y}$ can be represented by a *linear* map $[\mathbf{x}]_\times$ called the **hat map**

- The **hat map** $[\cdot]_\times : \mathbb{R}^3 \to \mathfrak{so}(3)$ transforms a vector $\mathbf{x} \in \mathbb{R}^3$ to a skew-symmetric matrix:

$$[\mathbf{x}]_\times := \begin{bmatrix} 0 & -x_3 & x_2 \\ x_3 & 0 & -x_1 \\ -x_2 & x_1 & 0 \end{bmatrix} \qquad\qquad [\mathbf{x}]_\times^\top = -[\mathbf{x}]_\times$$

- The vector space $\mathbb{R}^3$ and the space of skew-symmetric 3×3 matrices $\mathfrak{so}(3)$ are isomorphic, i.e., there exists a one-to-one map (the hat map) that preserves their structure.

Hat Map Properties

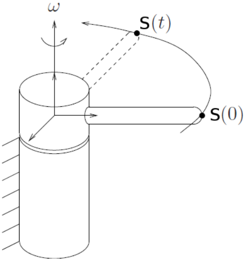
- **Lemma**: A matrix $M \in \mathbb{R}^{3\times 3}$ is skew-symmetric iff $M = [\mathbf{x}]_\times$ for some $\mathbf{x} \in \mathbb{R}^3$.

- The inverse of the hat map is the **vee map**, $\vee : \mathfrak{so}(3) \to \mathbb{R}^3$, that extracts the components of the vector $\mathbf{x} = [\mathbf{x}]_\times^\vee$ from the matrix $[\mathbf{x}]_\times$.

- For any $\mathbf{x}, \mathbf{y} \in \mathbb{R}^3$, $A \in \mathbb{R}^{3\times 3}$, the hat map satisfies:
  - $[\mathbf{x}]_\times \mathbf{y} = \mathbf{x} \times \mathbf{y} = -\mathbf{y} \times \mathbf{x} = -[\mathbf{y}]_\times \mathbf{x}$
  - $[\mathbf{x}]_\times^2 = \mathbf{x}\mathbf{x}^\top - \mathbf{x}^\top\mathbf{x}\, I_{3\times 3}$
  - $[\mathbf{x}]_\times^{2k+1} = (-\mathbf{x}^\top\mathbf{x})^k [\mathbf{x}]_\times$
  - $-\frac{1}{2}\operatorname{tr}([\mathbf{x}]_\times [\mathbf{y}]_\times) = \mathbf{x}^\top\mathbf{y}$
  - $[\mathbf{x}]_\times A + A^\top [\mathbf{x}]_\times = [(\operatorname{tr}(A) I_{3\times 3} - A)\mathbf{x}]_\times$
  - $\operatorname{tr}([\mathbf{x}]_\times A) = \frac{1}{2}\operatorname{tr}([\mathbf{x}]_\times (A - A^\top)) = -\mathbf{x}^\top (A - A^\top)^\vee$
  - $[A\mathbf{x}]_\times = \det(A) A^{-\top} [\mathbf{x}]_\times A^{-1}$

Axis-Angle Parametrization

- Every rotation can be represented as a rotation about an axis $\boldsymbol{\xi} \in \mathbb{R}^3$ through angle $\theta \in \mathbb{R}$
- The **axis-angle** parametrization can be combined in a single rotation vector $\boldsymbol{\theta} := \theta\boldsymbol{\xi} \in \mathbb{R}^3$
- Consider a point $\mathbf{s} \in \mathbb{R}^3$ rotating about an axis $\boldsymbol{\xi}$ at constant unit velocity:



$$\dot{\mathbf{s}}(t) = \boldsymbol{\xi} \times \mathbf{s}(t) = [\boldsymbol{\xi}]_\times \mathbf{s}(t), \quad \mathbf{s}(0) = \mathbf{s}_0$$

$$\Rightarrow \ \mathbf{s}(t) = e^{t[\boldsymbol{\xi}]_\times}\mathbf{s}_0 = R(t)\mathbf{s}_0 \quad \underset{t=\theta}{\overset{\text{unit velocity}}{\Rightarrow}} \quad R(\theta) = e^{\theta[\boldsymbol{\xi}]_\times}$$

- **Axis-angle representation**: a rotation around the axis $\boldsymbol{\xi} := \frac{\boldsymbol{\theta}}{\|\boldsymbol{\theta}\|_2}$ through an angle $\theta := \|\boldsymbol{\theta}\|_2$ can be represented as

$$R = \exp([\boldsymbol{\theta}]_\times) := \sum_{n=0}^{\infty} \frac{1}{n!}[\boldsymbol{\theta}]_\times^n = I + [\boldsymbol{\theta}]_\times + \frac{1}{2!}[\boldsymbol{\theta}]_\times^2 + \frac{1}{3!}[\boldsymbol{\theta}]_\times^3 + \dots$$

- **The matrix exponential defines a map from the space $\mathfrak{so}(3)$ of skew symmetric matrices to the space $SO(3)$ of rotation matrices**

Quaternions (Hamilton Convention)

- **Quaternions**: $\mathbb{H} = \mathbb{C} + \mathbb{C}j$ generalize complex numbers $\mathbb{C} = \mathbb{R} + \mathbb{R}i$

  $$\mathbf{q} = q_s + q_1 i + q_2 j + q_3 k = [q_s,\ \mathbf{q}_v] \qquad ij = -ji = k,\ i^2 = j^2 = k^2 = -1$$

- Just as in 2-D, 3-D rotations can be represented using "complex numbers", i.e., **unit-norm** quaternions $\{\mathbf{q} \in \mathbb{H} \mid q_s^2 + \mathbf{q}_v^T \mathbf{q}_v = 1\}$

- To represent rotations, the quaternion space embeds a 3-D space into a 4-D space (**no singularities**) and introduces a unit norm constraint.

- A rotation matrix $R \in SO(3)$ can be obtained from a unit quaternion $\mathbf{q}$:

  $$R(\mathbf{q}) = E(\mathbf{q})G(\mathbf{q})^\top \qquad \begin{aligned} E(\mathbf{q}) &= \left[-\mathbf{q}_v,\ q_s I + [\mathbf{q}_v]_\times\right] \\ G(\mathbf{q}) &= \left[-\mathbf{q}_v,\ q_s I - [\mathbf{q}_v]_\times\right] \end{aligned}$$

- The space of quaternions is a **double covering** of $SO(3)$ because two unit quaternions correspond to the same rotation: $R(\mathbf{q}) = R(-\mathbf{q})$.

Quaternion Conversions

- A rotation around a unit axis $\boldsymbol{\xi} := \frac{\boldsymbol{\theta}}{\|\boldsymbol{\theta}\|} \in \mathbb{R}^3$ by angle $\theta := \|\boldsymbol{\theta}\|$ can be represented by a unit quaternion:

$$\mathbf{q} = \left[\cos\left(\frac{\theta}{2}\right), \ \sin\left(\frac{\theta}{2}\right)\boldsymbol{\xi}\right]$$

- A rotation around a unit axis $\boldsymbol{\xi} \in \mathbb{R}^3$ by angle θ can be recovered from a unit quaternion $\mathbf{q}$:

$$\theta = 2\arccos(q_s) \qquad \boldsymbol{\xi} = \begin{cases} \frac{1}{\sin(\theta/2)}\mathbf{q}_v, & \text{if } \theta \neq 0 \\ 0, & \text{if } \theta = 0 \end{cases}$$

- The inverse transformation above has a singularity at $\theta = 0$ because there are infinitely many rotation axes that can be used or equivalently the transformation from an axis-angle representation to a quaternion representation is many-to-one

Quaternion Properties

Addition	$\mathbf{q}+\mathbf{p} := [q_s + p_s,\ \mathbf{q}_v + \mathbf{p}_v]$
Multiplication	$\mathbf{q}\circ\mathbf{p} := \left[q_s p_s - \mathbf{q}_v^T \mathbf{p}_v,\ q_s\mathbf{p}_v + p_s\mathbf{q}_v + \mathbf{q}_v \times \mathbf{p}_v\right]$
Conjugate	$\bar{\mathbf{q}} := [q_s,\ -\mathbf{q}_v]$
Norm	$\lVert\mathbf{q}\rVert := \sqrt{q_s^2 + \mathbf{q}_v^T\mathbf{q}_v} \qquad \lVert\mathbf{q}\circ\mathbf{p}\rVert = \lVert\mathbf{q}\rVert\lVert\mathbf{p}\rVert$
Inverse	$\mathbf{q}^{-1} := \frac{\bar{\mathbf{q}}}{\lVert\mathbf{q}\rVert^2}$
Rotation	$[0,\ \mathbf{x}'] = \mathbf{q}\circ[0,\ \mathbf{x}]\circ\mathbf{q}^{-1} = [0,\ R(\mathbf{q})\mathbf{x}]$
Velocity	$\dot{\mathbf{q}} = \frac{1}{2}\mathbf{q}\circ[0,\ \boldsymbol{\omega}] = \frac{1}{2}G(\mathbf{q})^T\boldsymbol{\omega}$
Exp	$\exp(\mathbf{q}) := e^{q_s}\left[\cos\lVert\mathbf{q}_v\rVert,\ \frac{\mathbf{q}_v}{\lVert\mathbf{q}_v\rVert}\sin\lVert\mathbf{q}_v\rVert\right]$
Log	$\log(\mathbf{q}) := \left[\log\lvert q\rvert,\ \frac{\mathbf{q}_v}{\lVert\mathbf{q}_v\rVert}\arccos\frac{q_s}{\lvert q\rvert}\right]$

- **Exp**: constructs $\mathbf{q}$ from rotation vector $\boldsymbol{\omega} \in \mathbb{R}^3$: $\mathbf{q} = \exp\left(\left[0,\ \frac{\boldsymbol{\omega}}{2}\right]\right)$
- **Log**: recovers a rotation vector $\boldsymbol{\omega} \in \mathbb{R}^3$ from $\mathbf{q}$: $[0,\ \boldsymbol{\omega}] = 2\log(\mathbf{q})$

Representations of Orientation (Summary)

- **Rotation Matrix**: an element of the **Special Orthogonal Group**:

$$R \in SO(3) := \left\{ R \in \mathbb{R}^{3\times 3} \;\middle|\; \underbrace{R^\top R = I}_{\text{distances preserved}}, \underbrace{\det(R) = 1}_{\text{no reflection}} \right\}$$

- **Euler Angles**: roll ϕ, pitch θ, roll ψ specifying a **rzyx** rotation:

$$R = R_z(\psi) R_y(\theta) R_x(\phi)$$

- **Axis-Angle**: $\boldsymbol{\theta} \in \mathbb{R}^3$ specifying a rotation about an axis $\boldsymbol{\xi} := \frac{\boldsymbol{\theta}}{\|\boldsymbol{\theta}\|}$ through an angle $\theta := \|\boldsymbol{\theta}\|$:

$$R = \exp([\boldsymbol{\theta}]_\times) = I + [\boldsymbol{\theta}]_\times + \frac{1}{2!}[\boldsymbol{\theta}]_\times^2 + \frac{1}{3!}[\boldsymbol{\theta}]_\times^3 + \dots$$

- **Unit Quaternion**: $\mathbf{q} = [q_s,\ \mathbf{q}_v] \in \left\{ q \in \mathbb{H} \mid q_s^2 + \mathbf{q}_v^T \mathbf{q}_v = 1 \right\}$:

$$R = E(\mathbf{q}) G(\mathbf{q})^\top \qquad \begin{aligned} E(\mathbf{q}) &= \left[-\mathbf{q}_v,\ q_s I + [\mathbf{q}_v]_\times\right] \\ G(\mathbf{q}) &= \left[-\mathbf{q}_v,\ q_s I - [\mathbf{q}_v]_\times\right] \end{aligned}$$

Example: Rotation with a Quaternion

- Let $\mathbf{x} = \mathbf{e}_2$ be a point in frame $\{A\}$.
- What are the coordinates of $\mathbf{x}$ in frame $\{B\}$ which is rotated by $\theta = \pi/3$ with respect to $\{A\}$ around the x-axis?
- The quaternion corresponding to the rotation from $\{B\}$ to $\{A\}$ is:

$$ {}_A\mathbf{q}_B = \begin{bmatrix} \cos(\theta/2) \\ \sin(\theta/2)\boldsymbol{\xi} \end{bmatrix} = \frac{1}{2}\begin{bmatrix} \sqrt{3} \\ \mathbf{e}_1 \end{bmatrix} $$

- The quaternion corresponding to the rotation from $\{A\}$ to $\{B\}$ is:

$$ {}_B\mathbf{q}_A = {}_A\mathbf{q}_B^{-1} = {}_A\bar{\mathbf{q}}_B = \frac{1}{2}\begin{bmatrix} \sqrt{3} \\ -\mathbf{e}_1 \end{bmatrix} $$

- The coordinates of $\mathbf{x}$ in frame $\{B\}$ are:

$$ \begin{aligned} {}_B\mathbf{q}_A \circ [0,\ \mathbf{x}] \circ {}_B\mathbf{q}_A^{-1} &= \frac{1}{4}\begin{bmatrix} \sqrt{3} \\ -\mathbf{e}_1 \end{bmatrix} \circ \begin{bmatrix} 0 \\ \mathbf{e}_2 \end{bmatrix} \circ \begin{bmatrix} \sqrt{3} \\ \mathbf{e}_1 \end{bmatrix} \\ &= \frac{1}{4}\begin{bmatrix} 0 \\ \sqrt{3}\mathbf{e}_2 - \mathbf{e}_1 \times \mathbf{e}_2 \end{bmatrix} \circ \begin{bmatrix} \sqrt{3} \\ \mathbf{e}_1 \end{bmatrix} = \frac{1}{2}\begin{bmatrix} 0 \\ \mathbf{e}_2 - \sqrt{3}\mathbf{e}_3 \end{bmatrix} \end{aligned} $$

Rigid Body Pose

- Let $\{B\}$ be a body frame whose position and orientation with respect to the world frame $\{W\}$ are $\mathbf{p} \in \mathbb{R}^3$ and $R \in SO(3)$, respectively.
- The coordinates of a point $\mathbf{s}_B \in \mathbb{R}^3$ can be converted to the world frame by first rotating the point and then translating it to the world frame:

$$\mathbf{s}_W = R\mathbf{s}_B + \mathbf{p}$$

- The **homogeneous coordinates** of a point $\mathbf{s} \in \mathbb{R}^3$ are

$$\underline{\mathbf{s}} := \lambda \begin{bmatrix} \mathbf{s} \\ 1 \end{bmatrix} \propto \begin{bmatrix} \mathbf{s} \\ 1 \end{bmatrix} \in \mathbb{R}^4$$

  The scale factor λ allows representing points arbitrarily far away from the origin as $\lambda \to 0$, e.g., $\underline{\mathbf{s}} = \begin{bmatrix} 1 & 2 & 1 & 0 \end{bmatrix}^\top$

- Rigid-body transformations are linear in homogeneous coordinates:

$$\underline{\mathbf{s}}_W = \begin{bmatrix} \mathbf{s}_W \\ 1 \end{bmatrix} = \begin{bmatrix} R & \mathbf{p} \\ \mathbf{0}^\top & 1 \end{bmatrix} \begin{bmatrix} \mathbf{s}_B \\ 1 \end{bmatrix} = T\underline{\mathbf{s}}_B$$

Special Euclidean Group $SE(3)$

- The pose T of a rigid body can be described by a matrix in the **special Euclidean group**:

$$SE(3) := \left\{ T := \begin{bmatrix} R & \mathbf{p} \\ \mathbf{0}^\top & 1 \end{bmatrix} \middle| \, R \in SO(3), \mathbf{p} \in \mathbb{R}^3 \right\} \subset \mathbb{R}^{4\times 4}$$

- It can be verified that $SE(3)$ satisfies all requirements of a group:
  - **Closure**: $T_1 T_2 = \begin{bmatrix} R_1 & \mathbf{p}_1 \\ \mathbf{0}^\top & 1 \end{bmatrix} \begin{bmatrix} R_2 & \mathbf{p}_2 \\ \mathbf{0}^\top & 1 \end{bmatrix} = \begin{bmatrix} R_1 R_2 & R_1 \mathbf{p}_2 + \mathbf{p}_1 \\ \mathbf{0}^\top & 1 \end{bmatrix} \in SE(3)$
  - **Identity**: $\begin{bmatrix} I & \mathbf{0} \\ \mathbf{0}^\top & 1 \end{bmatrix} \in SE(3)$
  - **Inverse**: $\begin{bmatrix} R & \mathbf{p} \\ \mathbf{0}^\top & 1 \end{bmatrix}^{-1} = \begin{bmatrix} R^T & -R^\top \mathbf{p} \\ \mathbf{0}^\top & 1 \end{bmatrix} \in SE(3)$
  - **Associativity**: $(T_1 T_2) T_3 = T_1 (T_2 T_3)$ for all $T_1, T_2, T_3 \in SE(3)$

Point Transformations

- Let the pose of a rigid body be ${}_{\{W\}}T_{\{B\}} := \begin{bmatrix} {}_{\{W\}}R_{\{B\}} & {}_{\{W\}}\mathbf{p}_{\{B\}} \\ \mathbf{0}^\top & 1 \end{bmatrix}$
- The subscripts indicate that **the pose of a rigid body in the world frame specifies a transformation from the body to the world frame**
- A point with body-frame coordinates $\mathbf{s}_B$, has world-frame coordinates:

$$\mathbf{s}_W = R\mathbf{s}_B + \mathbf{p} \quad \text{equivalent to} \quad \begin{bmatrix} \mathbf{s}_W \\ 1 \end{bmatrix} = \begin{bmatrix} R & \mathbf{p} \\ \mathbf{0}^\top & 1 \end{bmatrix} \begin{bmatrix} \mathbf{s}_B \\ 1 \end{bmatrix}$$

- A point with world-frame coordinates $\mathbf{s}_W$, has body-frame coordinates:

$$\begin{bmatrix} \mathbf{s}_B \\ 1 \end{bmatrix} = \begin{bmatrix} R & \mathbf{p} \\ \mathbf{0}^\top & 1 \end{bmatrix}^{-1} \begin{bmatrix} \mathbf{s}_W \\ 1 \end{bmatrix} = \begin{bmatrix} R^\top & -R^\top\mathbf{p} \\ \mathbf{0}^\top & 1 \end{bmatrix} \begin{bmatrix} \mathbf{s}_W \\ 1 \end{bmatrix}$$

Composing Transformations

- Give a robot with pose ${}_{\{W\}}T_{\{1\}}$ at time t_1 and ${}_{\{W\}}T_{\{2\}}$ at time t_2, the relative transformation from the inertial frame $\{2\}$ at time t_2 to the inertial frame $\{1\}$ at time t_1 is:

$$
\begin{aligned}
{}_{\{1\}}T_{\{2\}} &= {}_{\{1\}}T_{\{W\}}\ {}_{\{W\}}T_{\{2\}} = \left({}_{\{W\}}T_{\{1\}}\right)^{-1}\ {}_{\{W\}}T_{\{2\}} \\
&= \begin{bmatrix} {}_{\{W\}}R_{\{1\}}^{\top} & -{}_{\{W\}}R_{\{1\}}^{\top} \times {}_{\{W\}}\mathbf{p}_{\{1\}} \\ \mathbf{0}^{\top} & 1 \end{bmatrix} \begin{bmatrix} {}_{\{W\}}R_{\{2\}} & {}_{\{W\}}\mathbf{p}_{\{2\}} \\ \mathbf{0}^{\top} & 1 \end{bmatrix}
\end{aligned}
$$

- The pose $T(t_k) = T_k$ of a robot at time t_k always specifies a transformation from the body frame at time t_k to the world frame so we will not explicitly write the world frame subscript

- The relative transformation from inertial frame $\{2\}$ with world-frame pose T_2 to an inertial frame $\{1\}$ with world-frame pose T_1 is:

$$
{}_1T_2 = T_1^{-1}T_2
$$

Summary

	Rotation $SO(3)$	**Pose** $SE(3)$
Representation	$R : \begin{cases} R^T R = I \\ \det(R) = 1 \end{cases}$	$T = \begin{bmatrix} R & \mathbf{p} \\ \mathbf{0}^\top & 1 \end{bmatrix}$
Transformation	$\mathbf{s}_W = R\mathbf{s}_B$	$\mathbf{s}_W = R\mathbf{s}_B + \mathbf{p}$
Inverse	$R^{-1} = R^\top$	$T^{-1} = \begin{bmatrix} R^\top & -R^\top\mathbf{p} \\ \mathbf{0}^\top & 1 \end{bmatrix}$
Composition	${}_W R_B = {}_W R_A \, {}_A R_B$	${}_W T_B = {}_W T_A \, {}_A T_B$