

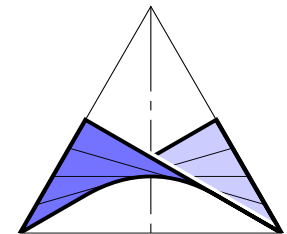
Symmetrische Rollungen mit sphärischen Punktbahnen

Symmetric Rollings with Spherical Trajectories

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Overview

1. Symmetric Rolling Motion
2. Basics on Hexapods and Self-Motions
3. Known Symmetric Rollings with Spherical Paths
4. Problem Formulation using Study Parameters
5. Duporcq Hexapod

Presented results are published in (and references are given with respect to):

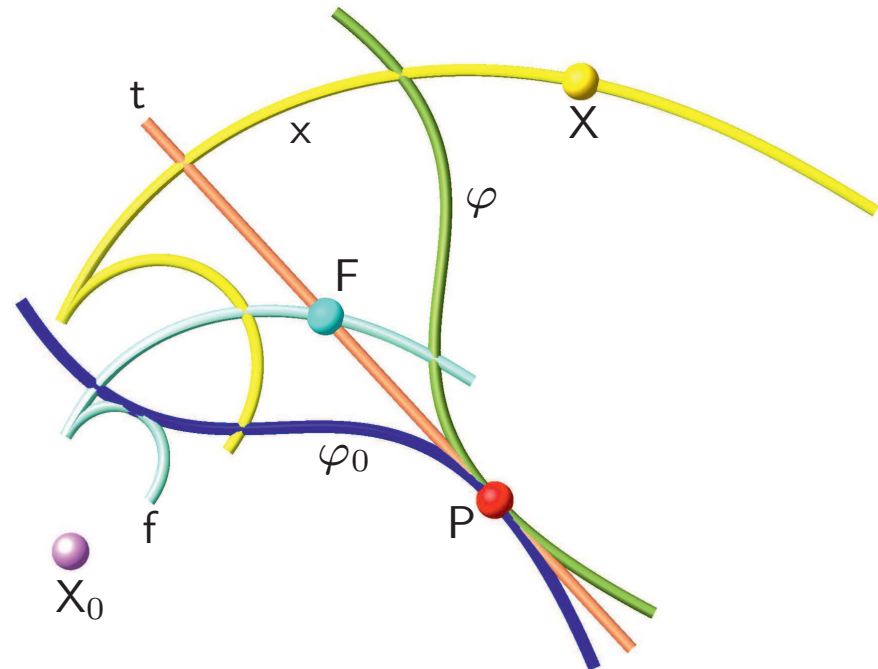
[G. NAWRATIL](#): Hexapods with plane-symmetric self-motions. In special issue Kinematics and Robot Design (R. Di Gregorio ed.), Robotics 7(2) #27 (2018)

1. Planar Symmetric Rolling

During the constrained motion of a planar mechanism the instantaneous pole P traces the so-called fixed/moving polode in the fixed/moving system.

It is well known that this motion can also be generated by the rolling of the moving polode φ along the fixed polode φ_0 without sliding.

If the polodes are symmetric with respect to the pole tangent t , then the motion is called *planar symmetric rolling*.



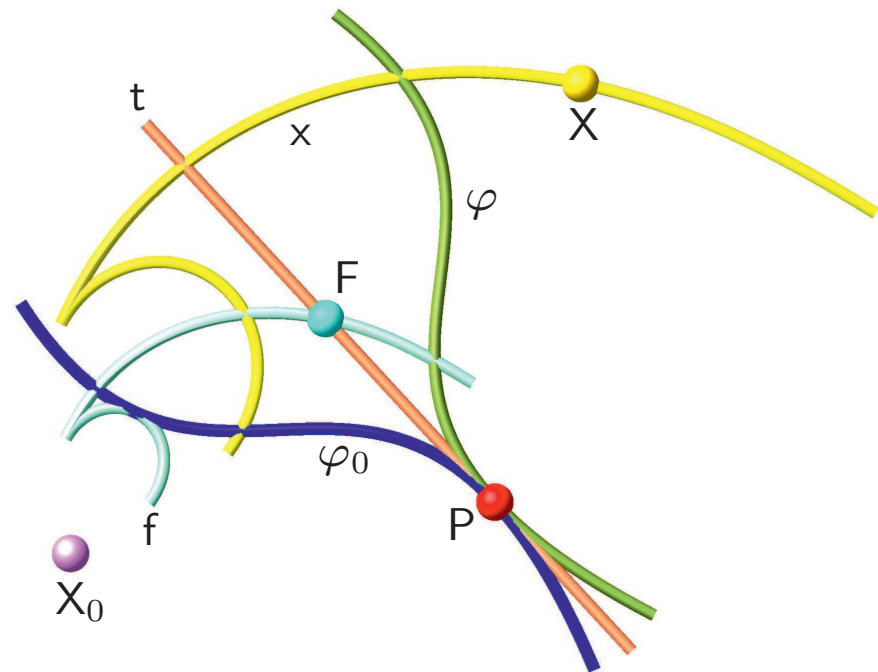
1. Planar Symmetric Rolling

In 1826, this motion was first studied by Quetelet [1], who pointed out that:

The path x of a point X under this special planar motion can be generated by the reflexion of a point X_0 of the fixed system on each tangent of φ_0 .

This can also be reformulated as follows:

x can be obtained by a central dilation with center X_0 and scale factor 2 (i.e., central doubling) of X_0 's pedal-curve f with respect to φ_0 .

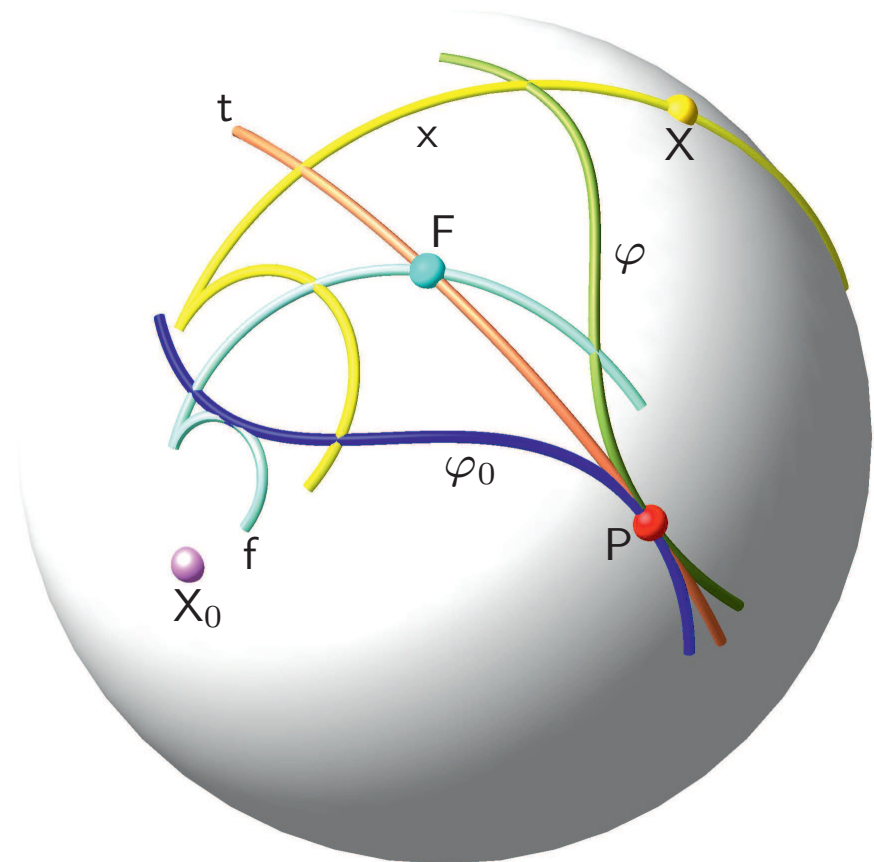


1. Spherical Symmetric Rolling

The spherical counterpart of this motion is called *spherical symmetric rolling* and was extensively studied by Tölke [2].

The spherical version of the above given characterization also holds true for the spherical symmetric rolling.

From another perspective, a planar/spherical symmetric rolling is generated by reflecting the fixed system in a 1-parametric continuous set of lines/great circles.



1. Spatial Generalization of Symmetric Rollings

The latter point of view is of importance for the spatial generalization of symmetric rollings, which can be done in multiple ways:

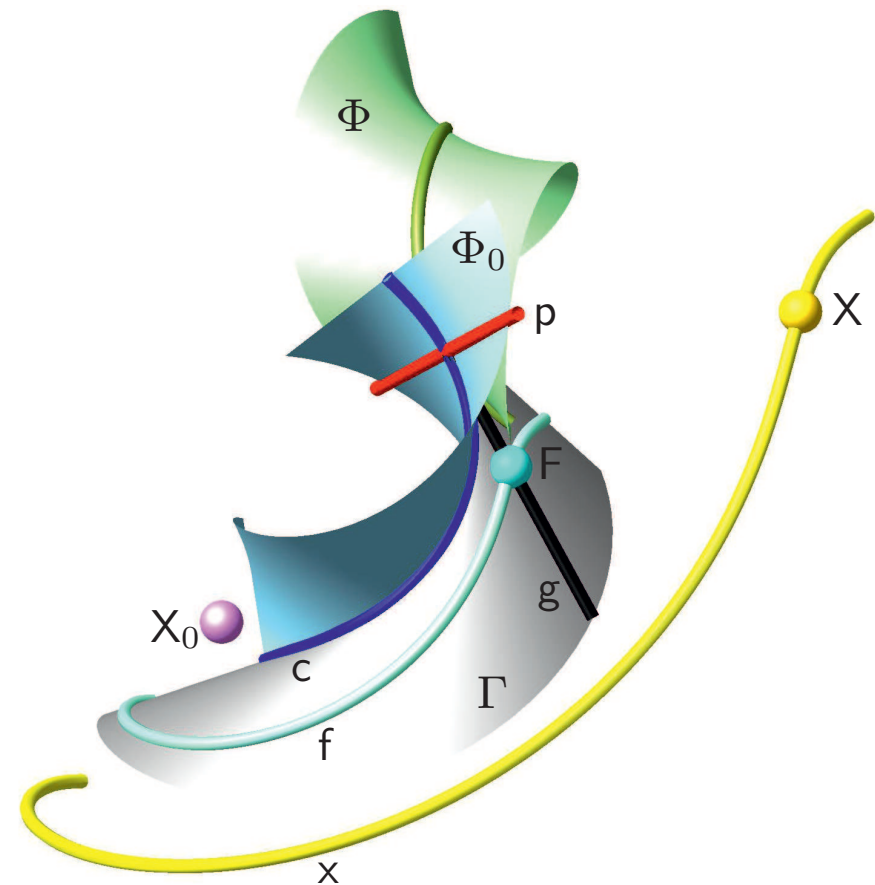
1. Darboux [5] noted a 2-parametric spatial motion, which is generated by the rolling of a moving surface Φ on an indirect congruent fixed surface Φ_0 .

It also holds that the path-surface of a point X can be generated by the reflexion of a point X_0 of the fixed system on each tangent-plane of Φ_0 ; i.e. the path-surface can be obtained by a central doubling of X_0 's pedal-surface with respect to Φ_0 's tangent-planes.

1. Spatial Generalization of Symmetric Rollings

2. Krames [6] considered line-symmetric motions as the 1-parametric spatial analogue. These motions are obtained by reflecting the moving system in a 1-parametric set of lines forming the so-called *basic surface* Γ .

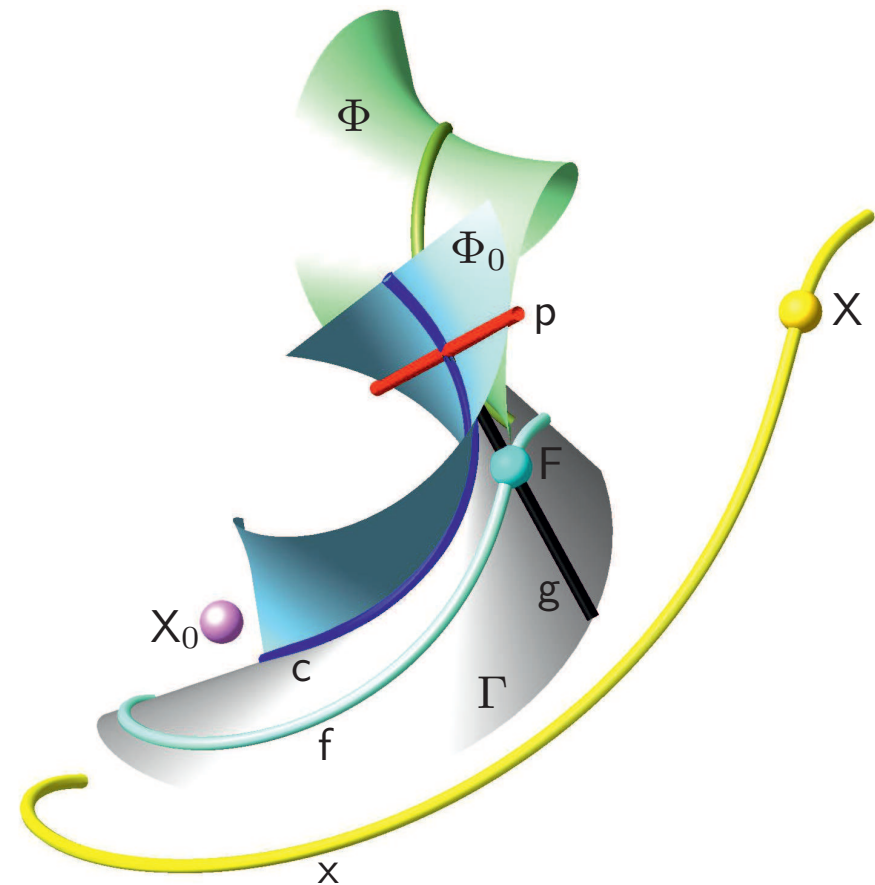
The path x of a point X under a line-symmetric motion can be generated by the reflexion of a point X_0 on each generator g of Γ ; i.e. x can be obtained by a central doubling of X_0 's pedal-curve f with respect to Γ 's rulings.



1. Spatial Generalization of Symmetric Rollings

However, it should be pointed out that Γ differs from the fixed axode Φ_0 , which is generated by Γ 's central tangents (i.e. common normals of infinitesimal neighboring lines of Γ).

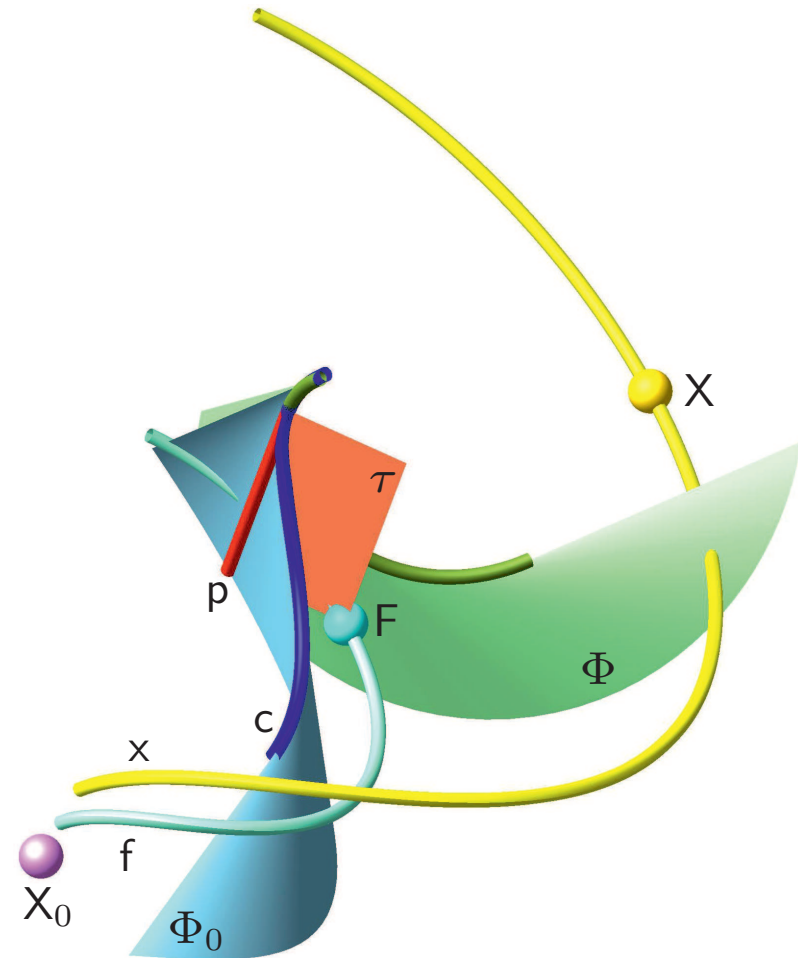
Φ_0 and the moving axode Φ are at each time instant symmetric with respect to the axis p of the instantaneous screw, which is in general not an instantaneous rotation.



1. Spatial Generalization of Symmetric Rollings

3. It is astonishing that neither Tölke [2] nor Krames [6] mentioned the more apparent generalization by reflecting the fixed system in a 1-parametric continuous set of planes.

Less attention was paid to these so-called *plane-symmetric motions* in the literature until now. The basic properties of this motion type were reported by Bottema and Roth [8].

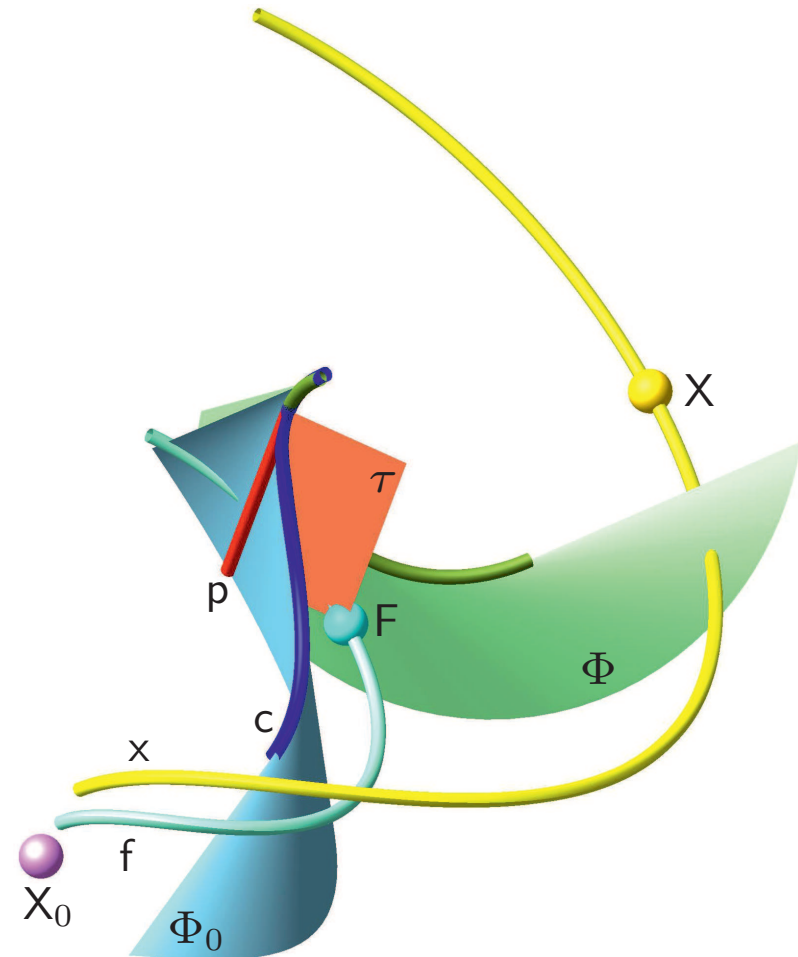


1. Plane-Symmetric Motion

Given is a 1-parametric continuous set of planes $\tau(t)$ with time t . By reflecting the fixed frame $\mathfrak{F}_0$ on the plane $\tau(t)$, we obtain the pose $\mathfrak{F}_0^t$.

Two infinitesimal neighboring poses $\mathfrak{F}_0^t$ and $\mathfrak{F}_0^{t+\Delta t}$ can be transformed into each other by a reflexion on $\tau(t)$ followed by a further reflexion on $\tau(t + \Delta t)$.

This is a pure rotation about the line p of intersection of $\tau(t)$ and $\tau(t + \Delta t)$.

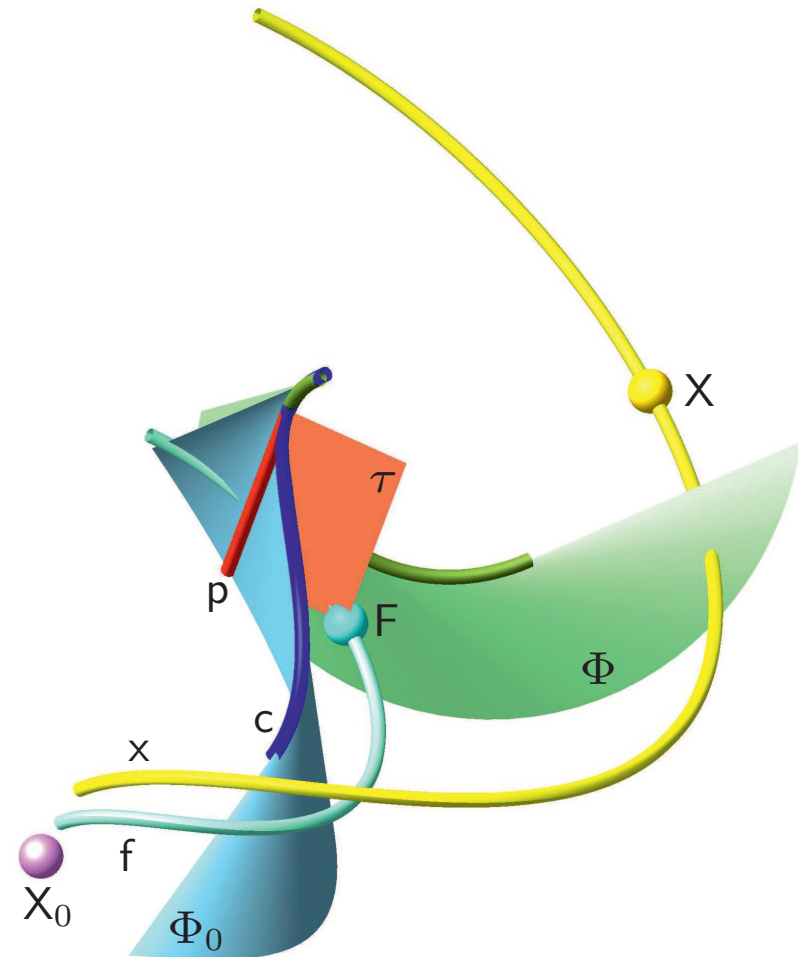


1. Plane-Symmetric Motion

The axis p of this instantaneous rotation is a torsal ruling of the surface enveloped by the given 1-parametric set of planes.

Therefore the fixed axode Φ_0 is a developable surface and the corresponding moving axode Φ is obtained by reflecting Φ_0 in Φ_0 's tangent-plane τ along p .

The path x of a point X under a plane-symmetric motion can be generated by the reflexion of a point X_0 on each tangent-plane τ of Φ_0



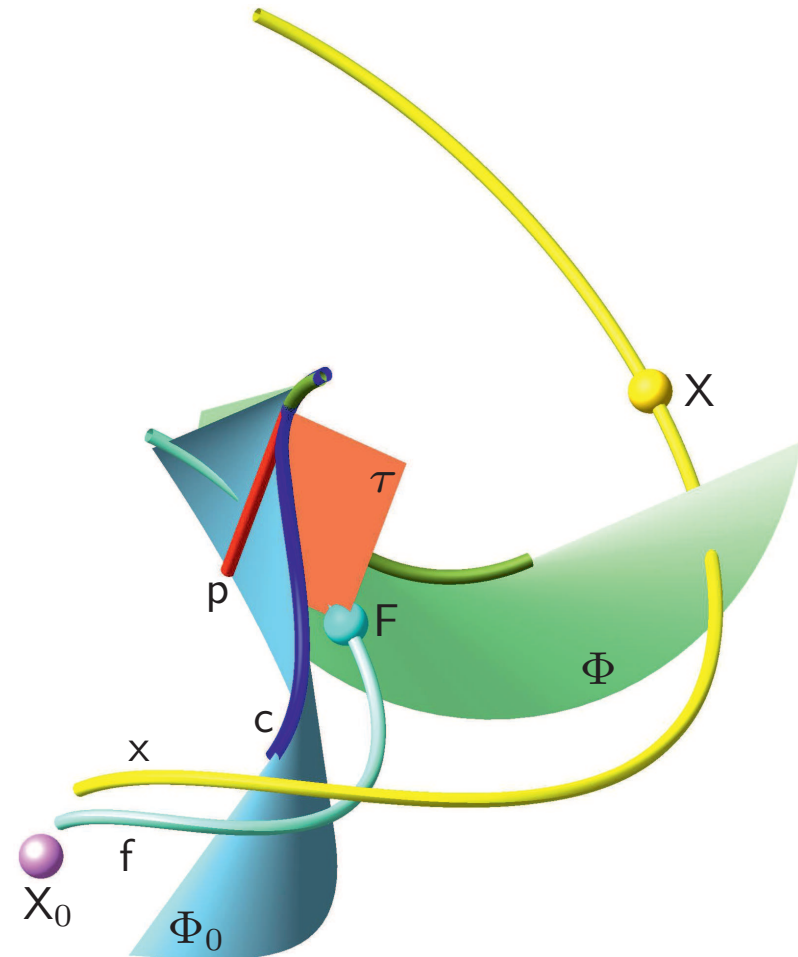
1. Plane-Symmetric Motion

This can also be reformulated as follows:

x can be obtained by a central doubling of X_0 's pedal-curve f with respect to Φ 's tangent-planes.

Due to these properties, the plane-symmetric motion is the straightforward spatial counterpart of the planar/spherical symmetric rolling.

Therefore the plane-symmetric motion is also called *spatial symmetric rolling*.

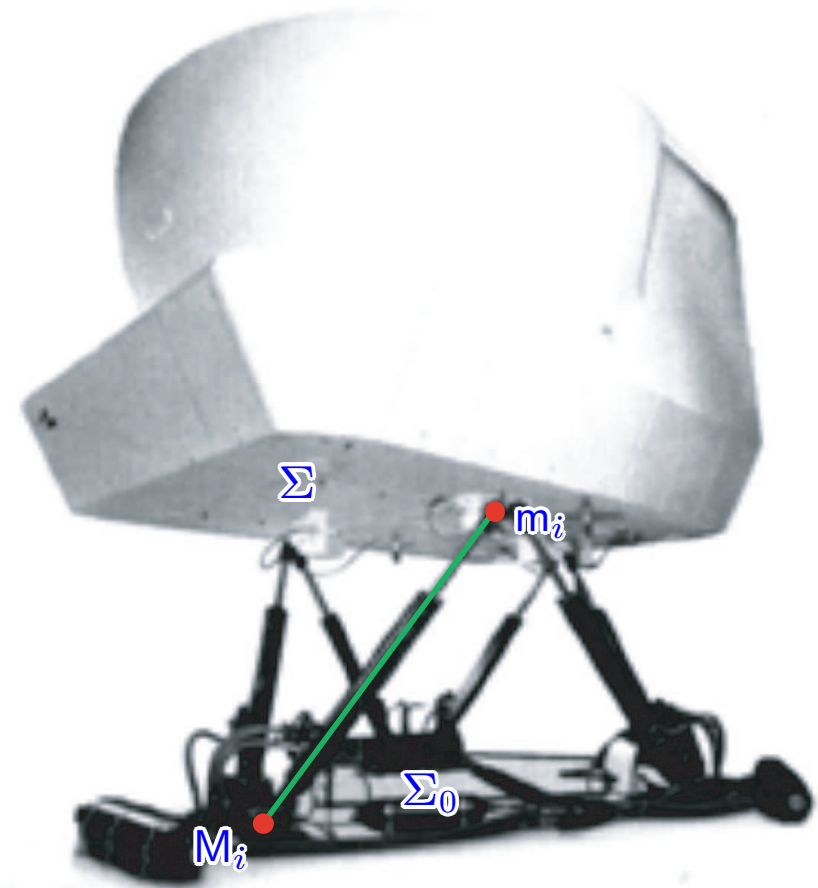


2. Basics on Hexapods and Self-Motions

A hexapod consists of a moving platform Σ and the fixed base Σ_0 , which are linked with six legs anchored via spherical joints.

The geometry of a hexapod is given by the six base anchor points $M_i \in \Sigma_0$ and by the six platform points $m_i \in \Sigma$.

For fixed leg lengths a hexapod is in general rigid. But, in some particular cases the hexapod can perform an n -parametric motion ($n > 0$), which is called *self-motion*.

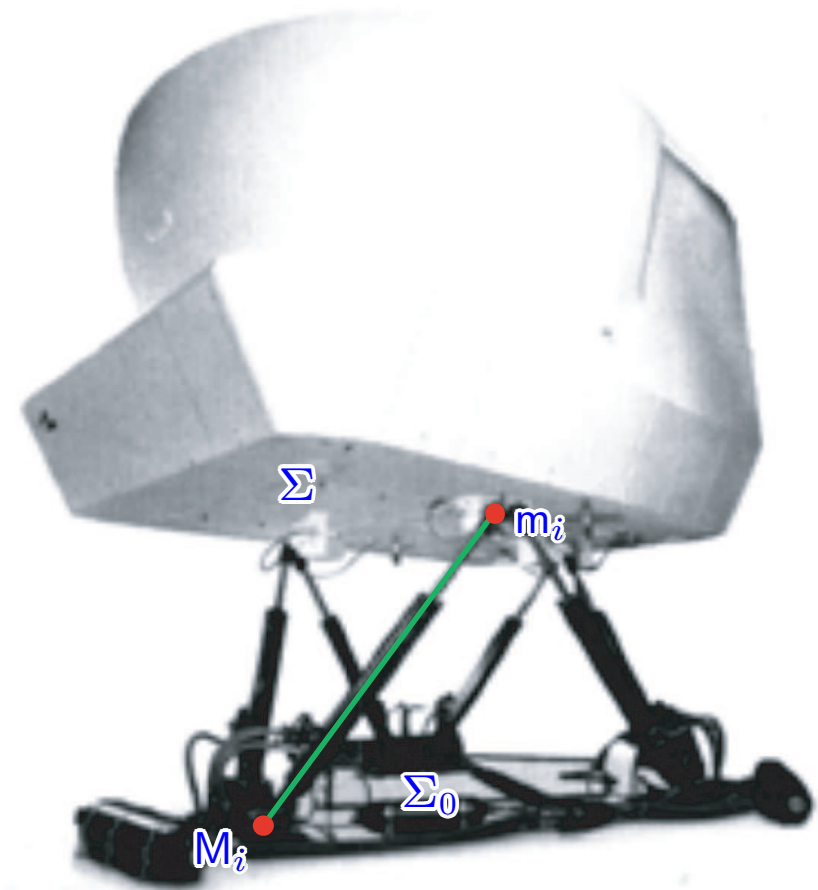


2. Basics on Hexapods and Self-Motions

All self-motions are solutions to the problem posed by the French Academy of Science for the *Prix Vaillant* (1904), also known as

Borel–Bricard problem (still unsolved)
Determine and study all displacements of a rigid body in which distinct points of the body move on spherical paths.

Clearly, in each pose of a self-motion the hexapod has to be *infinitesimal flexible*.

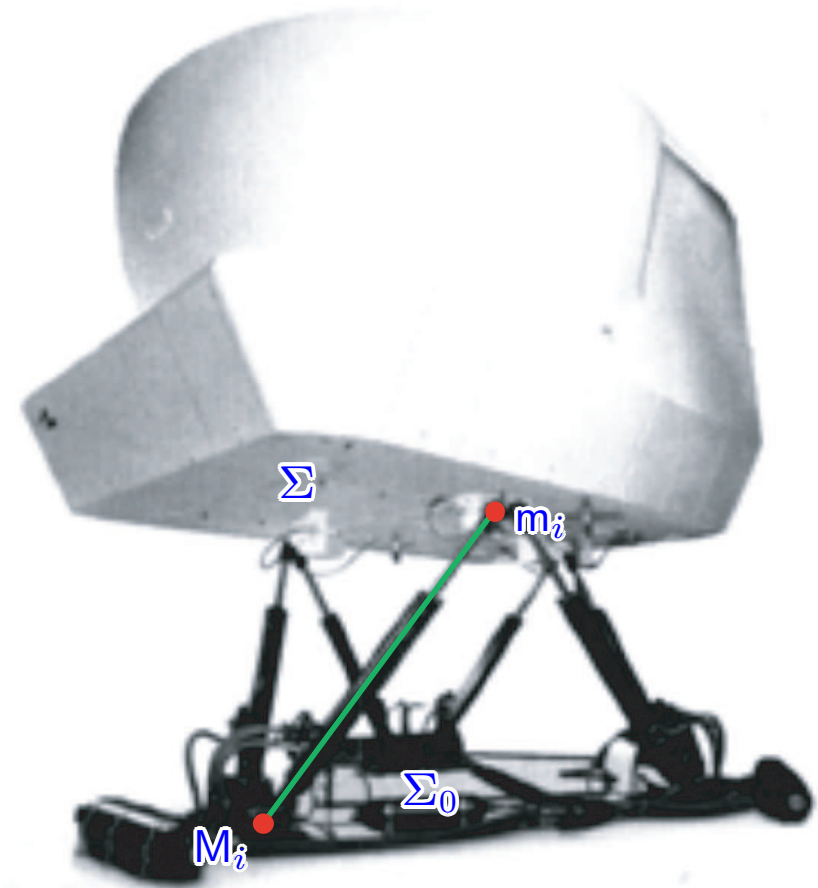


2. Basics on Hexapods and Self-Motions

A hexapod is *singular* (*infinitesimal flexible, shaky*), if and only if, the carrier lines of the six legs belong to a linear line complex.

A hexapod is called *architecturally singular* if the six legs belong in each relative pose of the platform with respect to the base to a linear line complex.

These special solutions to the Borel–Bricard problem are already well studied (review on this topic is given in [15]).



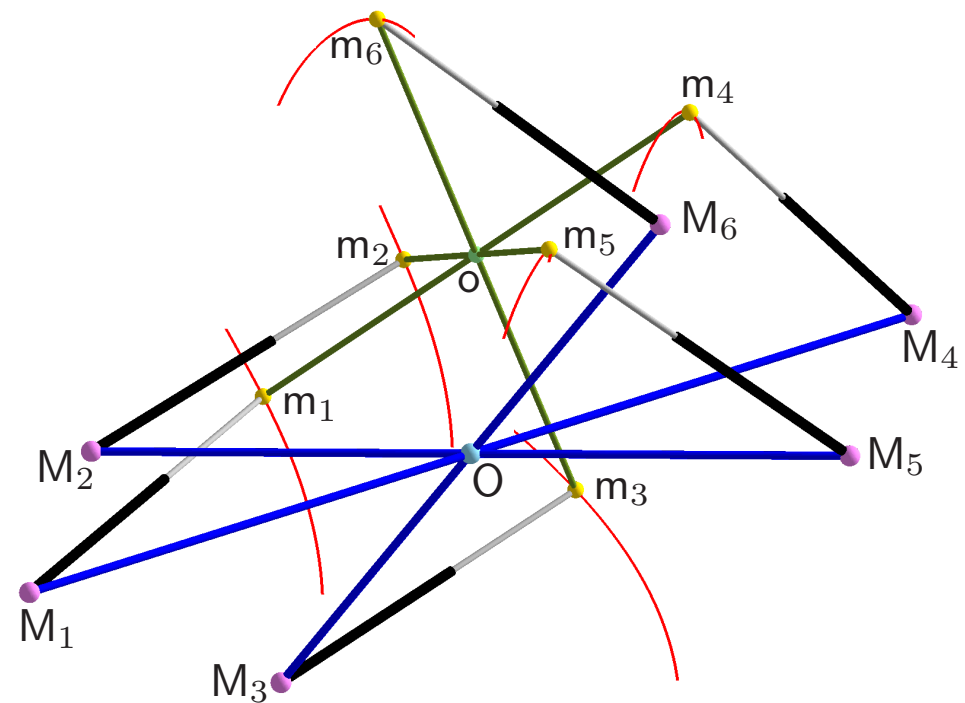
2. Basics on Hexapods and Self-Motions

The approaches for the determination of non-architecturally singular hexapods recorded in the literature, can roughly be divided into the following two groups:

1. Assumptions on the geometry of the platform and base; e.g.,

- ★ linear mapping between platform and base [16–22],
- ★ symmetry properties of platform and base [20–24] (cf. Figure),
- ★ special topology (e.g. octahedral structure [25]),

or a combination of these assumptions (e.g. [20–22]).

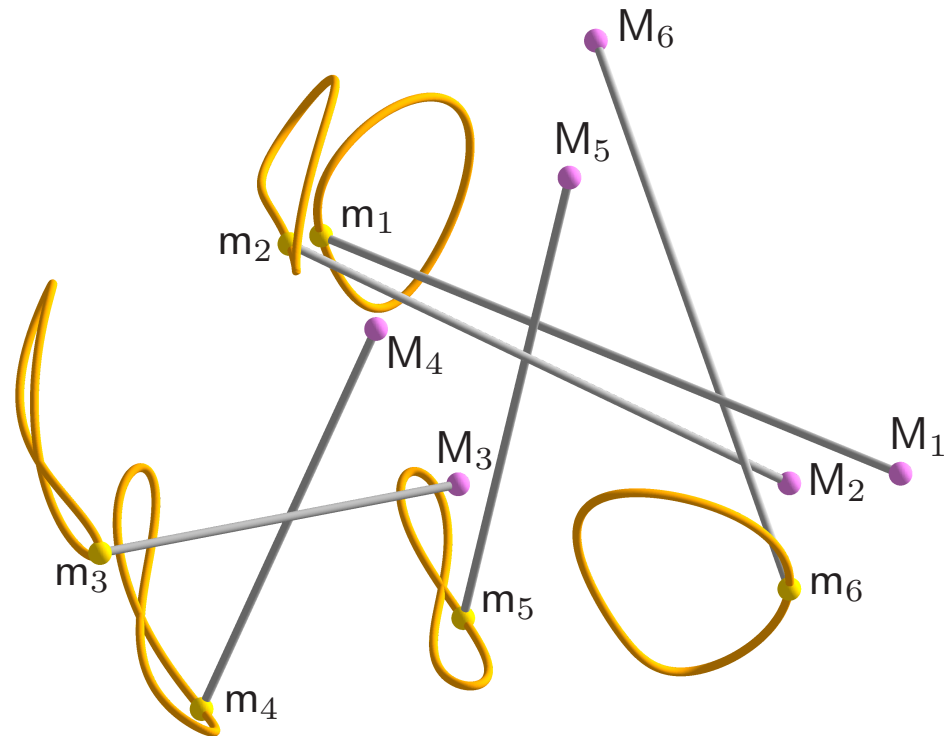


2. Basics on Hexapods and Self-Motions

2. Assumptions on the self-motion; e.g.,

- ★ line-symmetric self-motion [9],
- ★ type II Darboux–Mannheim self-motion [26],
- ★ Schoenflies self-motion [27],
- ★ translational self-motion [28],
- ★ self-motion of maximal degree [29] (cf. Figure),

or more generally characterizations like *linear relations between direction cosines* [30–33].



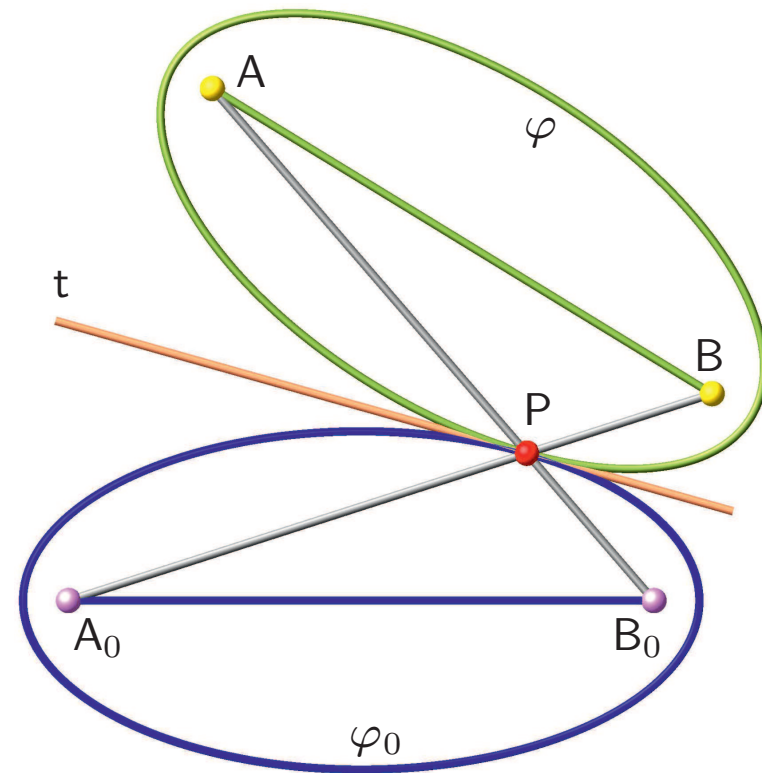
These assumptions are done to reduce the complexity of the problem, as one has to deal with 29 design parameters and 6 degrees of freedom.

3. Planar Symmetric Rollings with Circular Paths

All planar symmetric rollings with points running on circular paths were determined by Bereis [3].

- a) The polodes are ellipses and the focals of the moving ellipse are running on circles.

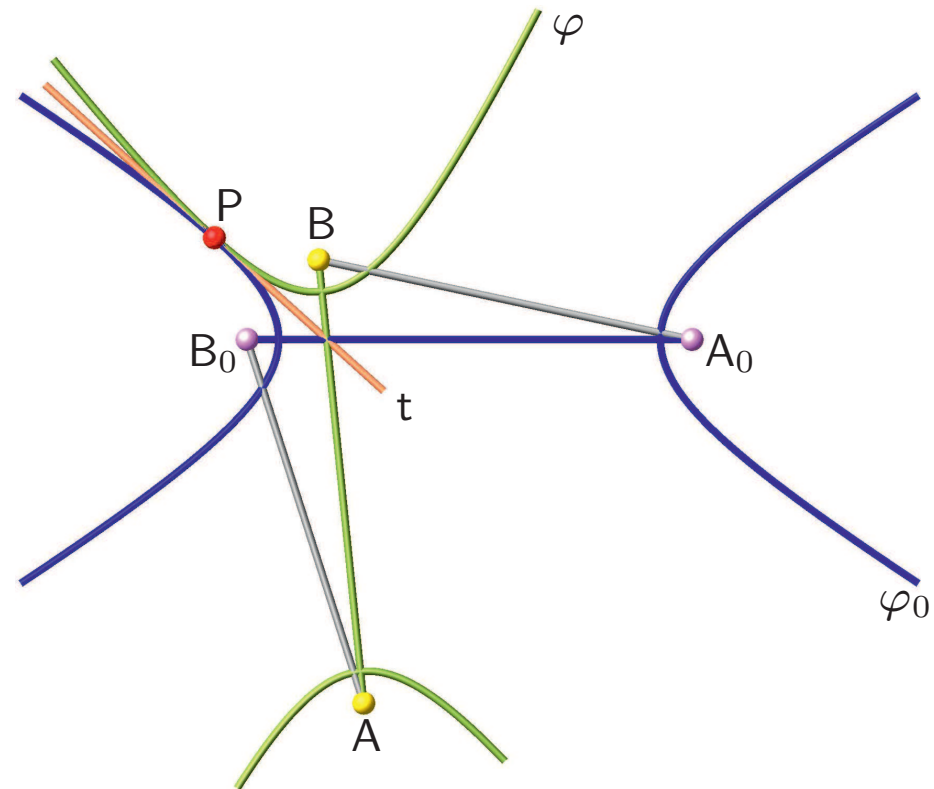
This motion can be realized by a twin-crank mechanisms with non-counter-rotating cranks.



3. Planar Symmetric Rollings with Circular Paths

- b) The polodes are hyperbolas and the focals of the moving hyperbola are running on circles.

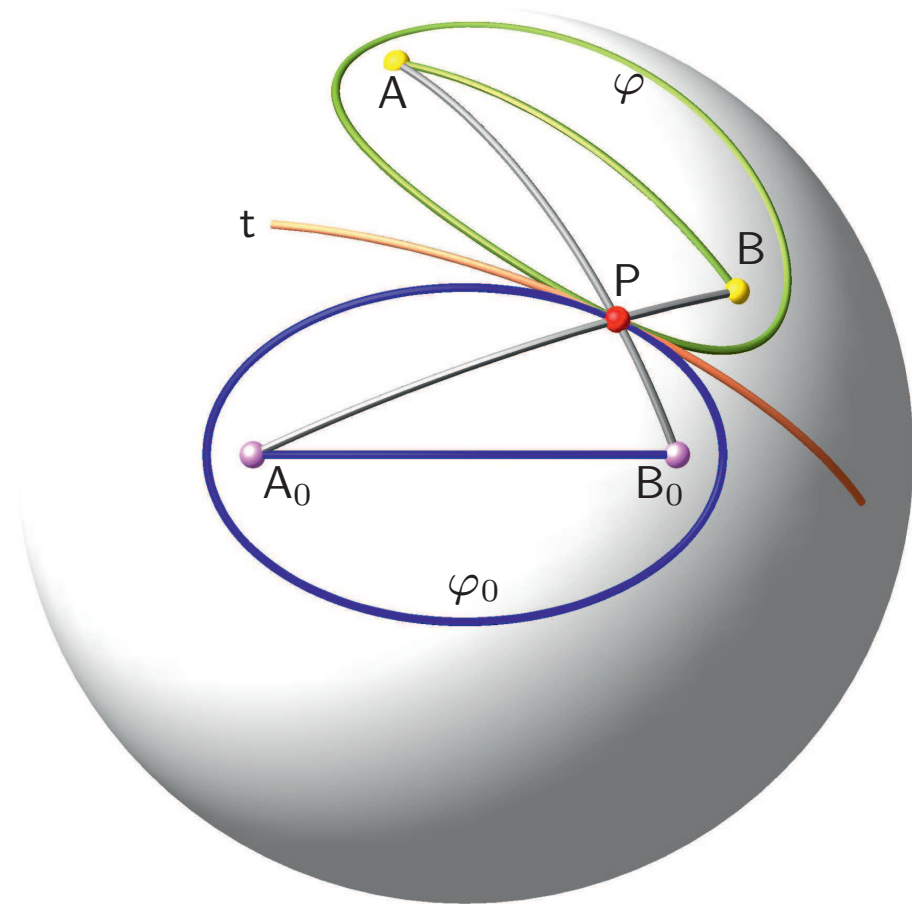
This motion can be realized by a twin-crank mechanisms with counter-rotating cranks.



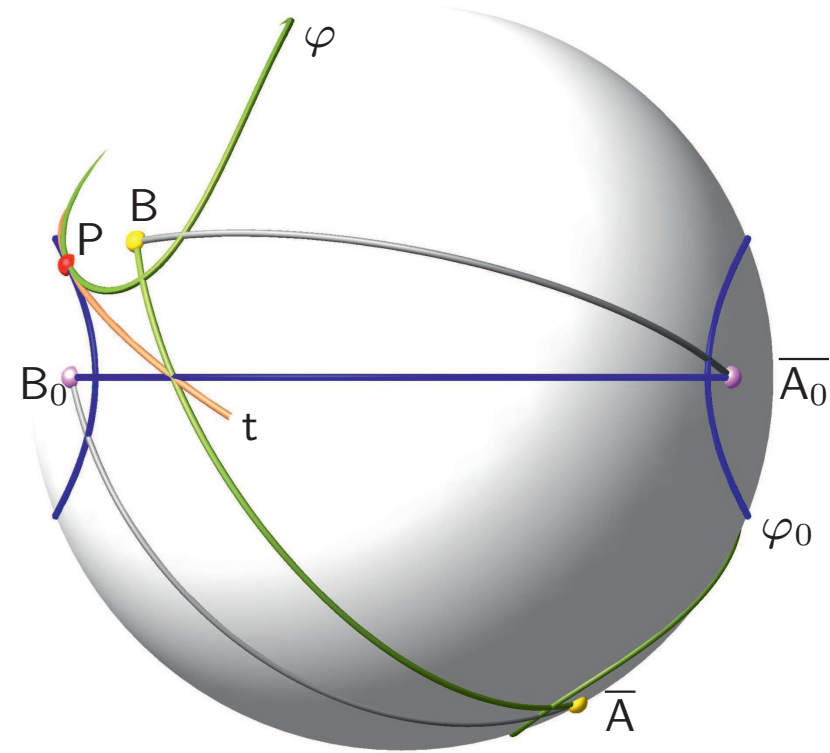
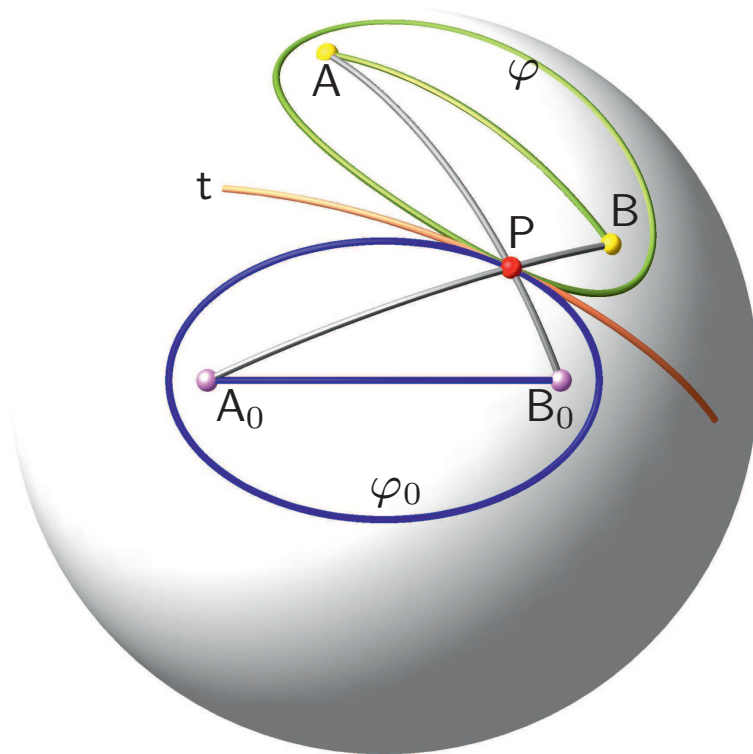
3. Spherical Symmetric Rollings with Circular Paths

Spherical symmetric rollings with circular paths are generated by spherical isograms, which are studied in more detail in [34].

The moving and fixed polode are spherical conics. As on the sphere points can be replaced by their antipodes, it can be shown [35] that every spherical conic can be interpreted as a spherical ellipse.

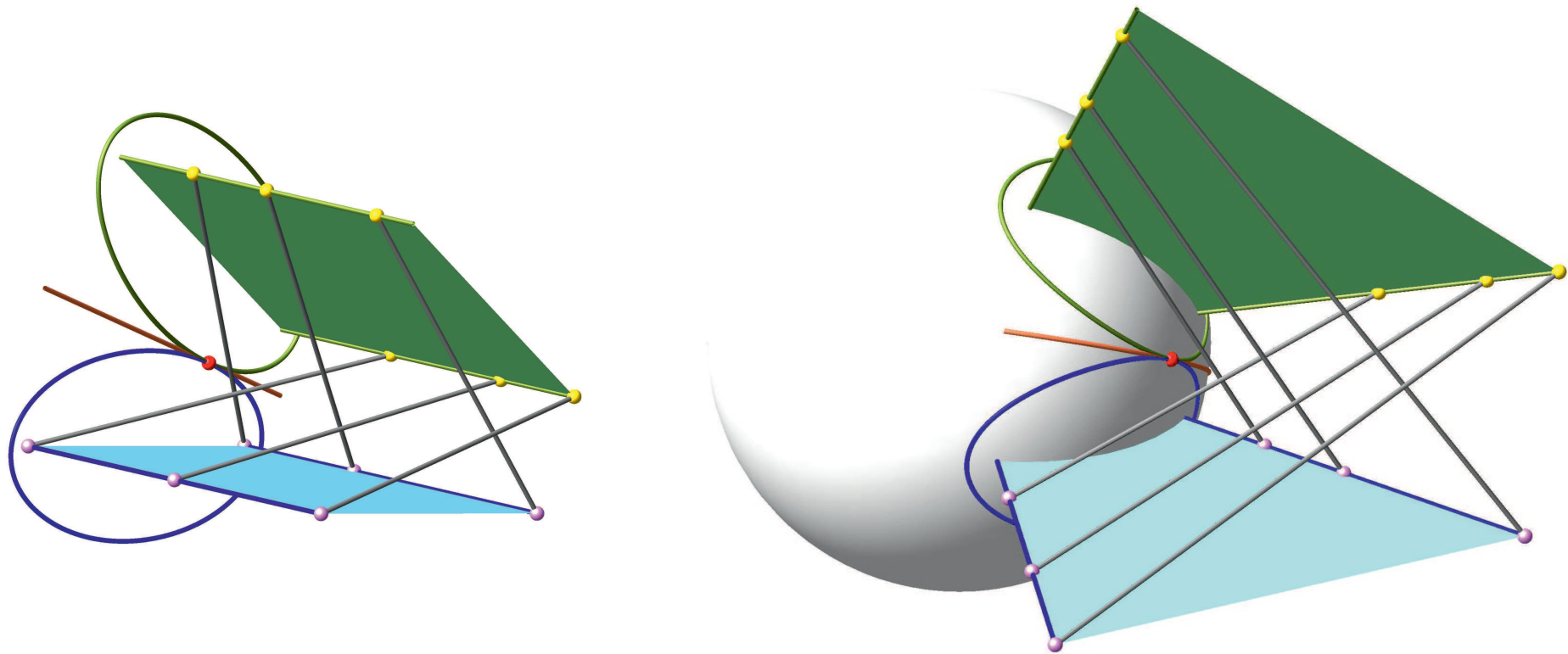


3. Spherical Symmetric Rollings with Circular Paths



If we replace A and A_0 by their antipodal points $\bar{A}$ and $\bar{A}_0$, respectively, and look on the sphere from the right side, then we get the figure illustrated on the right.

3. Resulting Hexapods with Symmetric Self-Motions



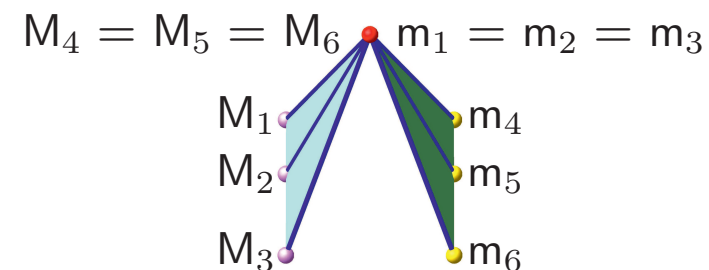
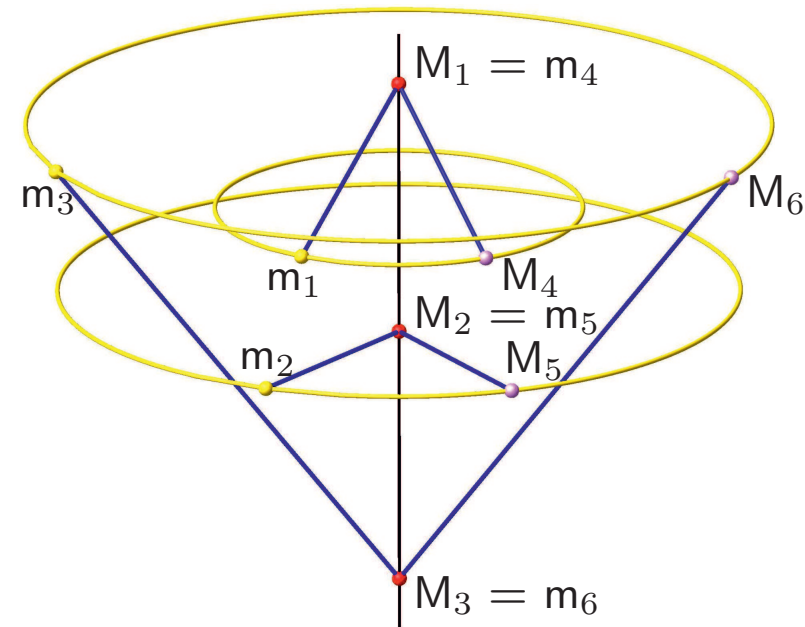
The axodes of the self-motions are cylinders (left) and cones (right), respectively, but only the planar/spherical directrices of these singular quadrics are illustrated.

3. Hexapods with Trivial Symmetric Self-Motions

Clearly, a pure rotation is a symmetric rolling where every point of the moving system traces a circle. This trivial case (butterfly self-motion) arises for:

- ★ $M_1, \dots, M_i$ are collinear and
 - ★ $m_{i+1}, \dots, m_6$ are collinear
- with $1 \leq i \leq 5$.

If the collinearity is replaced by coincidence then there exists even a 2-dimensional spherical self-motion.



3. Known Self-Motions are Line-Symmetric

If we embed the planar/spherical symmetric rollings into the group $SE(3)$ of Euclidean displacements, then they can also be seen as line-symmetric motions.

Therefore, all the self-motions of the hexapods given so far are symmetric rollings and line-symmetric motions at the same time.

This raises also the question of whether self-motions exist, which are symmetric rollings but not line-symmetric.

An answer can be obtained by formulating the problem in terms of algebraic geometry by means of Study parameters $(e_0 : e_1 : e_2 : e_3 : f_0 : f_1 : f_2 : f_3)$.

4. Problem Formulation using Study Parameters

There is a bijection between $SE(3)$ and real points of the 7-dimensional Study parameter space P^7 , which are located on the so-called Study quadric $\Psi : \sum_{i=0}^3 e_i f_i = 0$ sliced along the 3-dimensional subspace $e_0 = e_1 = e_2 = e_3 = 0$.

For $e_0^2 + e_1^2 + e_2^2 + e_3^2 = 1$ the translation vector $\mathbf{t} := (t_1, t_2, t_3)^T$ and the rotation matrix $\mathbf{R} := (r_{ij})$ of the corresponding Euclidean displacement $\mathbf{x} \mapsto \mathbf{R}\mathbf{x} + \mathbf{t}$ are given by:

$$t_1 = 2(e_0 f_1 - e_1 f_0 + e_2 f_3 - e_3 f_2),$$

$$t_2 = 2(e_0 f_2 - e_2 f_0 + e_3 f_1 - e_1 f_3),$$

$$t_3 = 2(e_0 f_3 - e_3 f_0 + e_1 f_2 - e_2 f_1),$$

$$\mathbf{R} = \begin{pmatrix} e_0^2 + e_1^2 - e_2^2 - e_3^2 & 2(e_1 e_2 - e_0 e_3) & 2(e_1 e_3 + e_0 e_2) \\ 2(e_1 e_2 + e_0 e_3) & e_0^2 - e_1^2 + e_2^2 - e_3^2 & 2(e_2 e_3 - e_0 e_1) \\ 2(e_1 e_3 - e_0 e_2) & 2(e_2 e_3 + e_0 e_1) & e_0^2 - e_1^2 - e_2^2 + e_3^2 \end{pmatrix}.$$

4. Problem Formulation using Study Parameters

The reflection on a plane is an orientation-reversing congruence transformation, which cannot be described directly by the Study parameters. Therefore, we follow the approach of Selig and Husty [7], which is as follows:

- We start with a reflexion on a fixed plane; say the xy -plane of the fixed frame $\mathfrak{F}_0$. By this plane-reflection of $\mathfrak{F}_0$, we obtain $\bar{\mathfrak{F}}_0$.
- Then we apply the reflexion on the plane $\tau(t)$, which finally yields the pose $\bar{\mathfrak{F}}_0^t$.

As the composition of two plane-reflexions is again a direct congruence transformation, we can describe the plane-symmetric motions in this way.

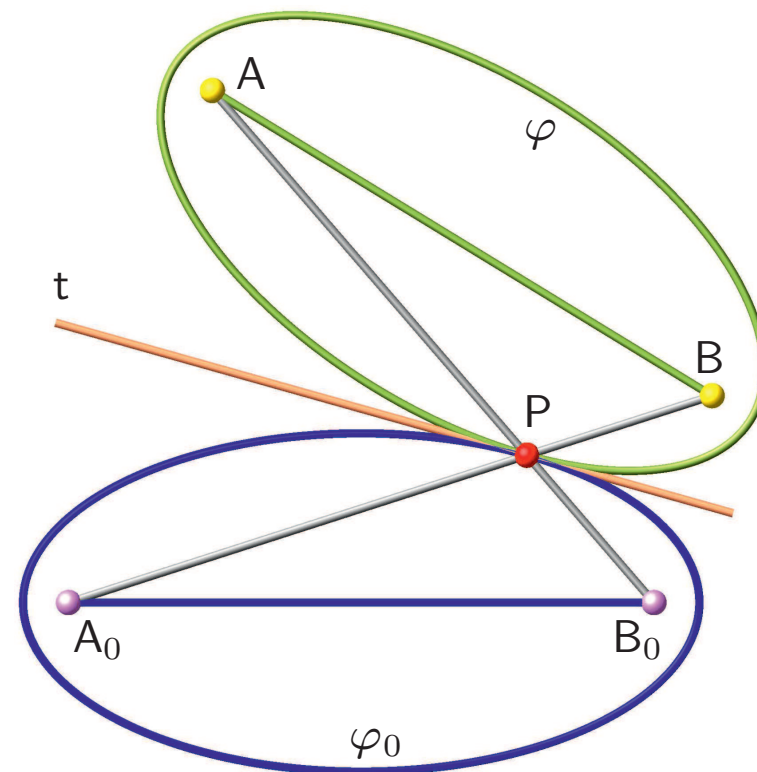
As a consequence plane-symmetric motions are given by $e_3 = f_0 = f_1 = f_2 = 0$; i.e. this corresponds to a 3-dimensional generator space P^3 of Ψ .

4. Symmetric Rollings with Spherical Paths

Due to the symmetry of the motion the following theorem holds:

Theorem 2. If a point A of the moving system traces a spherical path with center B_0 during a symmetric rolling, then also the point B of the moving system has a spherical trajectory about the point A_0 , where A and A_0 as well as B and B_0 are the symmetric points of the moving and fixed system.

Due to this symmetric-leg replacement the set of base points and platform points are indirectly congruent.



4. Spatial Symmetric Rollings with Spherical Paths

The condition that the point m_i is located on a sphere centered in M_i is a quadratic homogeneous equation in the Study parameters according to Husty [36].

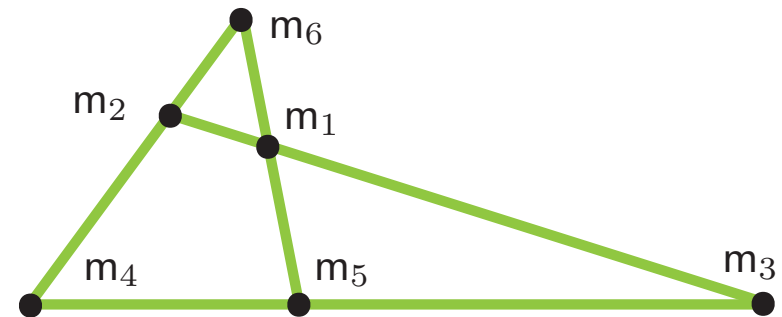
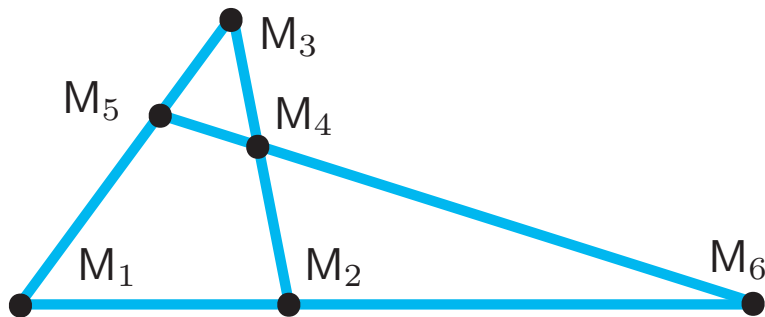
Therefore it corresponds to a quadric Λ_i in the 3-dimensional projective space P^3 with homogenous coordinates $(e_0 : e_1 : e_2 : f_3)$.

Due to the symmetric-leg replacement, we only have to find spatial rolling motions where three points run on spheres. This means that the corresponding three quadrics Λ_1 , Λ_2 and Λ_3 of P^3 have to have a curve in common, which can be a:

★ straight line ★ conic section ★ cubic curve ★ quartic curve

5. Duporcq Hexapod

A discussion of cases shows that there exists only one further hexapod with plane-symmetric self-motions, which are neither planar nor spherical. This manipulator is the so-called *Duporcq hexapod*.

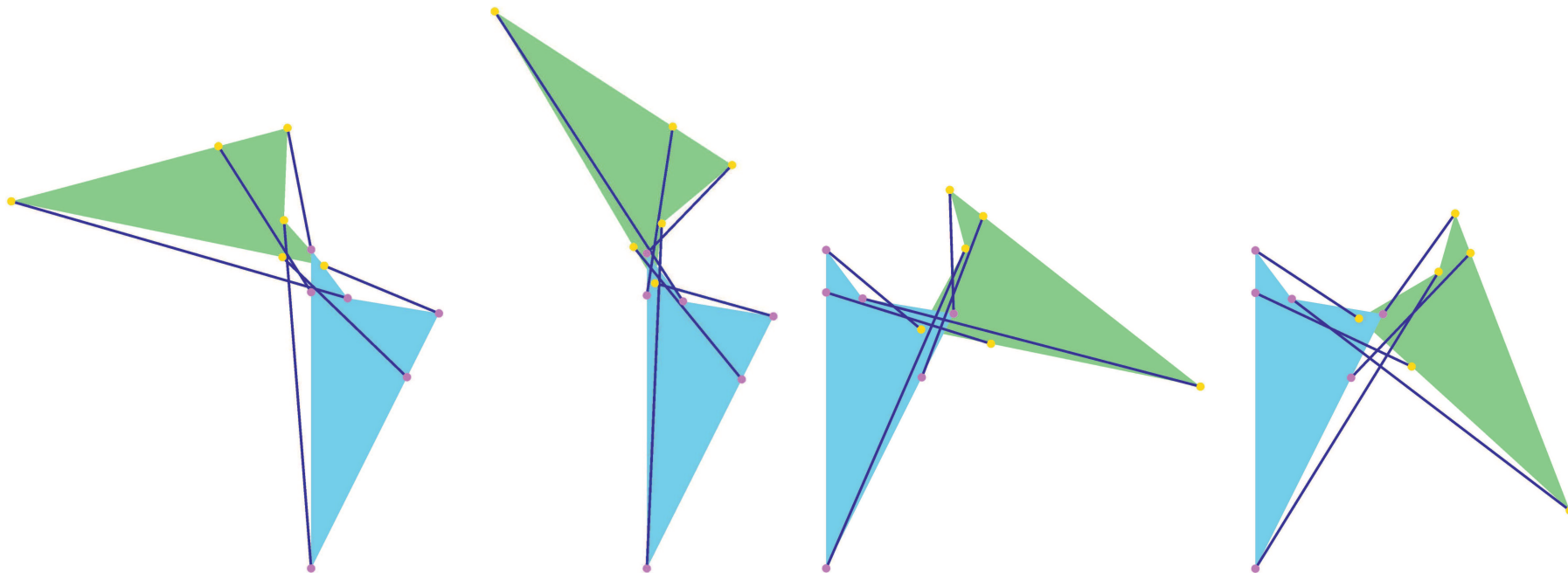


$M_1, \dots, M_6$ and $m_1, \dots, m_6$ be the vertices of two congruent complete quadrilaterals, which are labeled in a way that m_i is the opposite vertex of M_i .

It is well known [39] that the Duporcq hexapod is architecturally singular.

5. Duporcq Hexapod

Due to Duporcq [38] this hexapod has a 2-parametric line-symmetric self-motion. There are four transition poses between this line-symmetric self-motion and the 1-parametric plane-symmetric self-motion. All four branching singularities are totally flat configurations.



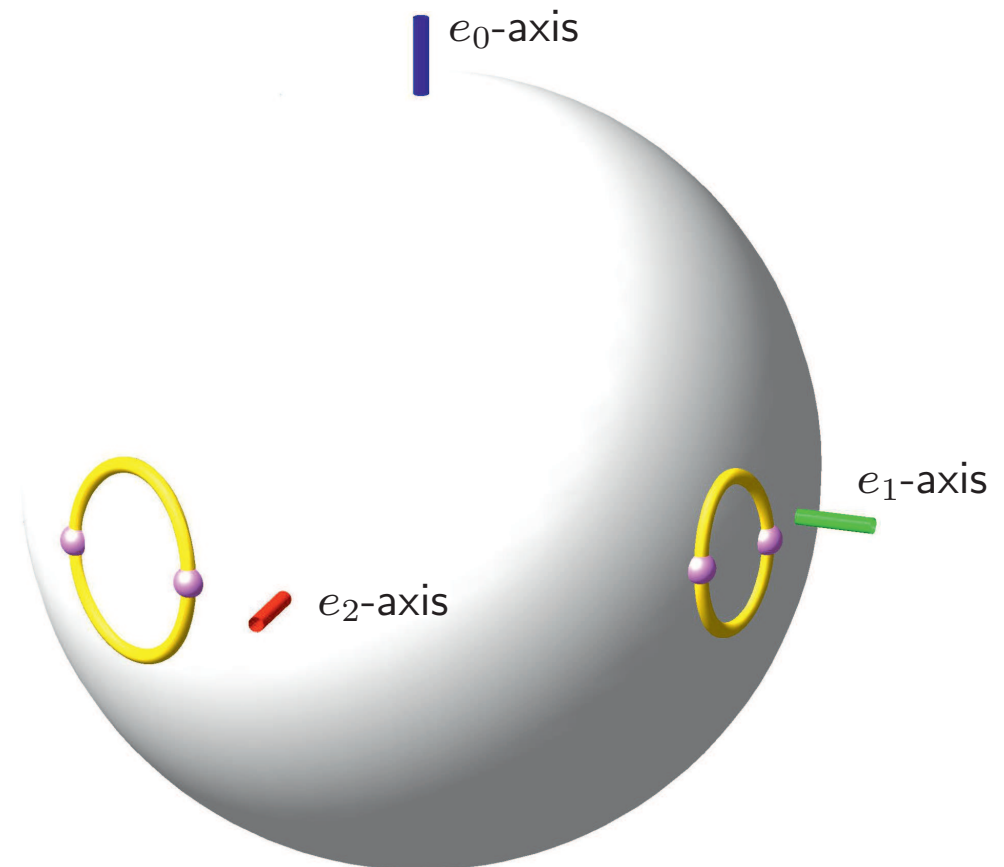
5. Duporcq Hexapod

Recall that the sphere condition Λ_i is a homogenous quadratic equation in e_0, e_1, e_2, f_3 .

We express f_3 from the condition $\Lambda_2 - \Lambda_1$, which is linear in f_3 .

Plugging the resulting expression into Λ_1 implies a homogenous quartic equation Υ in e_0, e_1, e_2 , which represents the plane-symmetric self-motion.

The quartic Υ is displayed under consideration of the normalization condition $e_0^2 + e_1^2 + e_2^2 = 1$.

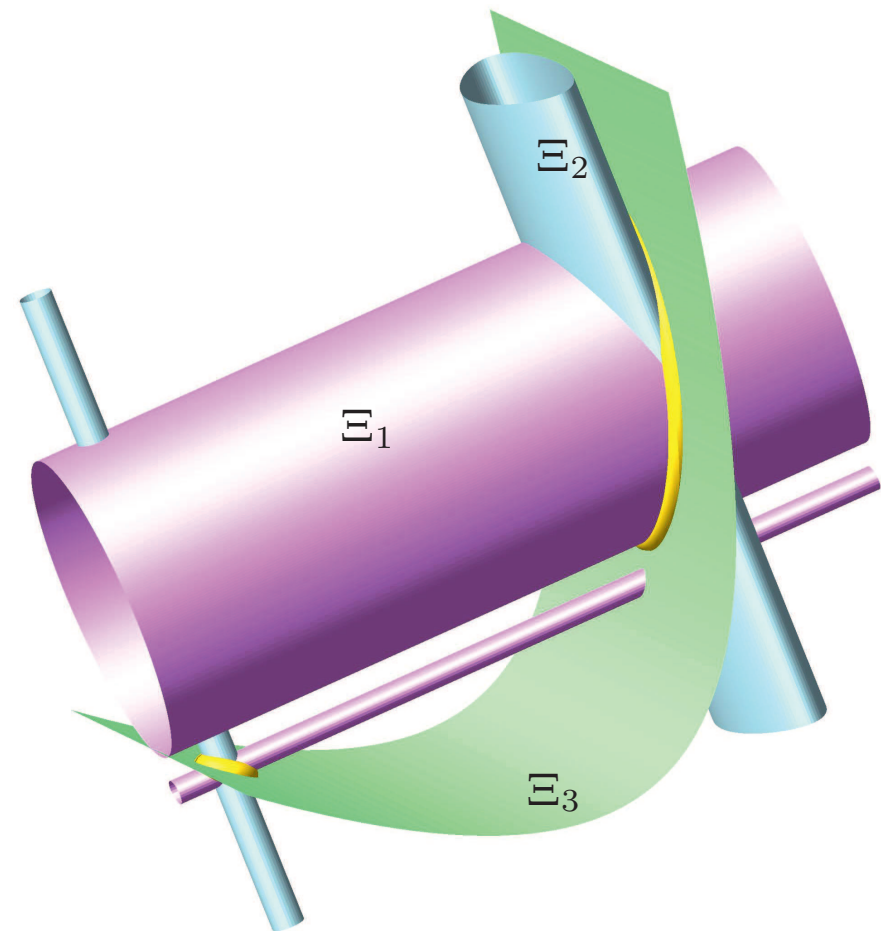


5. Duporcq Hexapod

If $ax + by + cz + d = 0$ is the equation of the plane of symmetry, then its dual representation is given by the homogeneous quadruplet $(u_0 : u_1 : u_2 : u_3) = (d : a : b : c)$ according to [11].

The fixed axode corresponds to an algebraic curve of degree 4 in the dual representation, which results from the intersection of two cylinders of degree 4 and one quadratic cylinder.

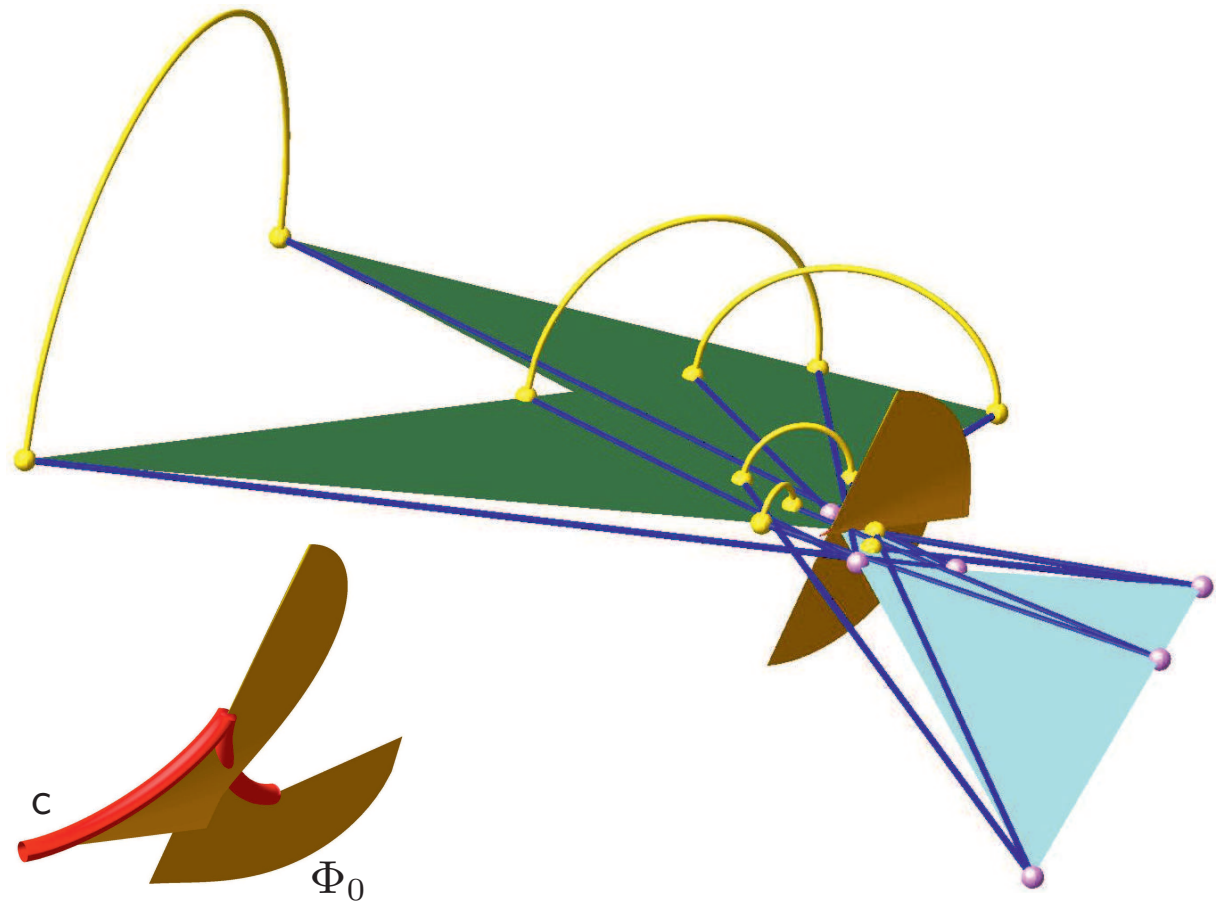
This curve can be parametrized (two branches).



5. Duporcq Hexapod

Trajectories of the platform points during the plane-symmetric self-motion between the totally flat transition poses 1 and 2.

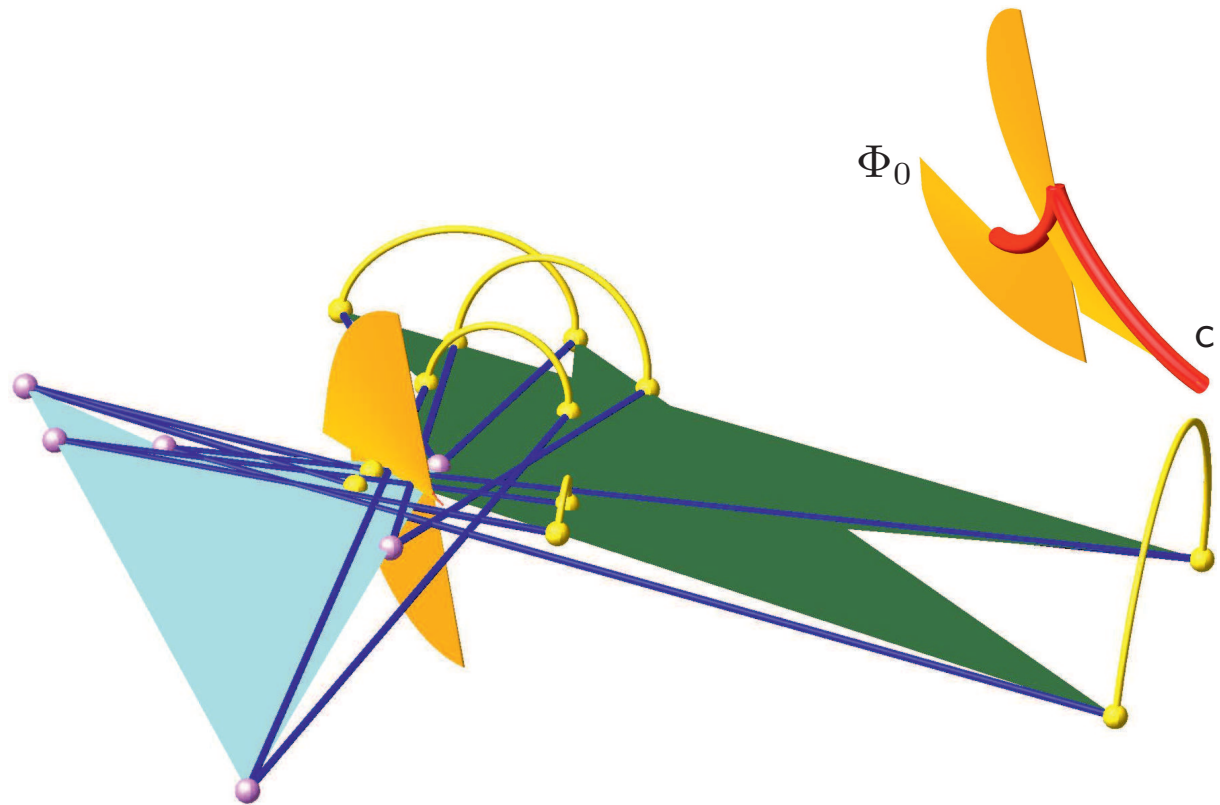
In the lower left corner a blow up of the fixed axode Φ_0 (including its line of regression c) is displayed.



5. Duporcq Hexapod

Trajectories of the platform points during the plane-symmetric self-motion between the totally flat transition poses 3 and 4.

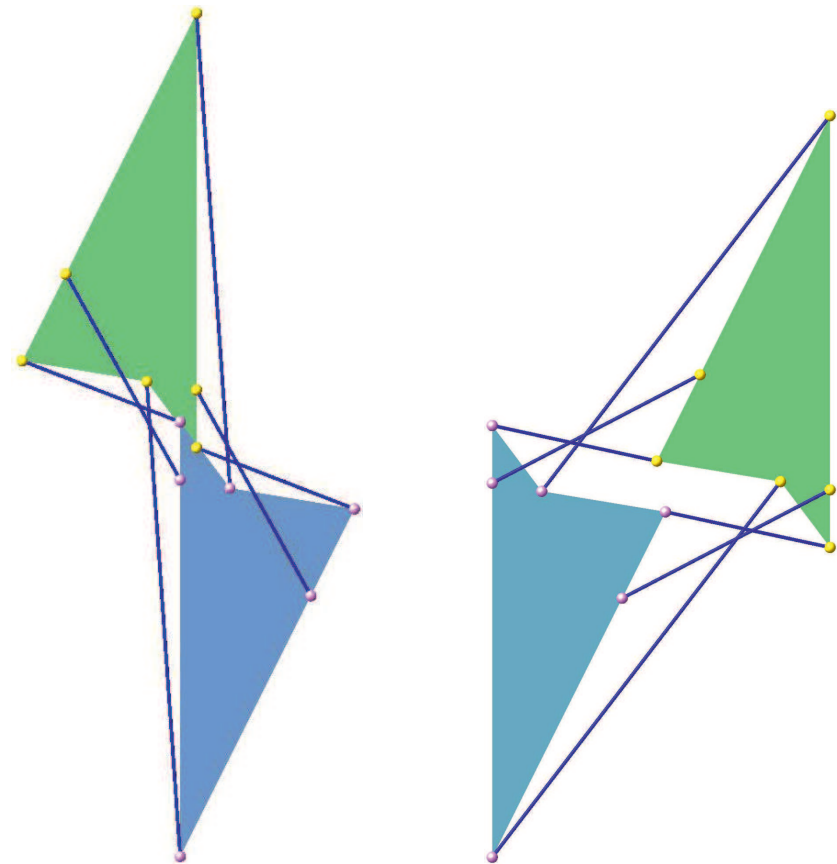
In the upper right corner a blow up of the fixed axode Φ_0 (including its line of regression c) is displayed.



5. Duporcq Hexapod

The Duporcq manipulator also has a 1-parametric translational self-motion (circular translation).

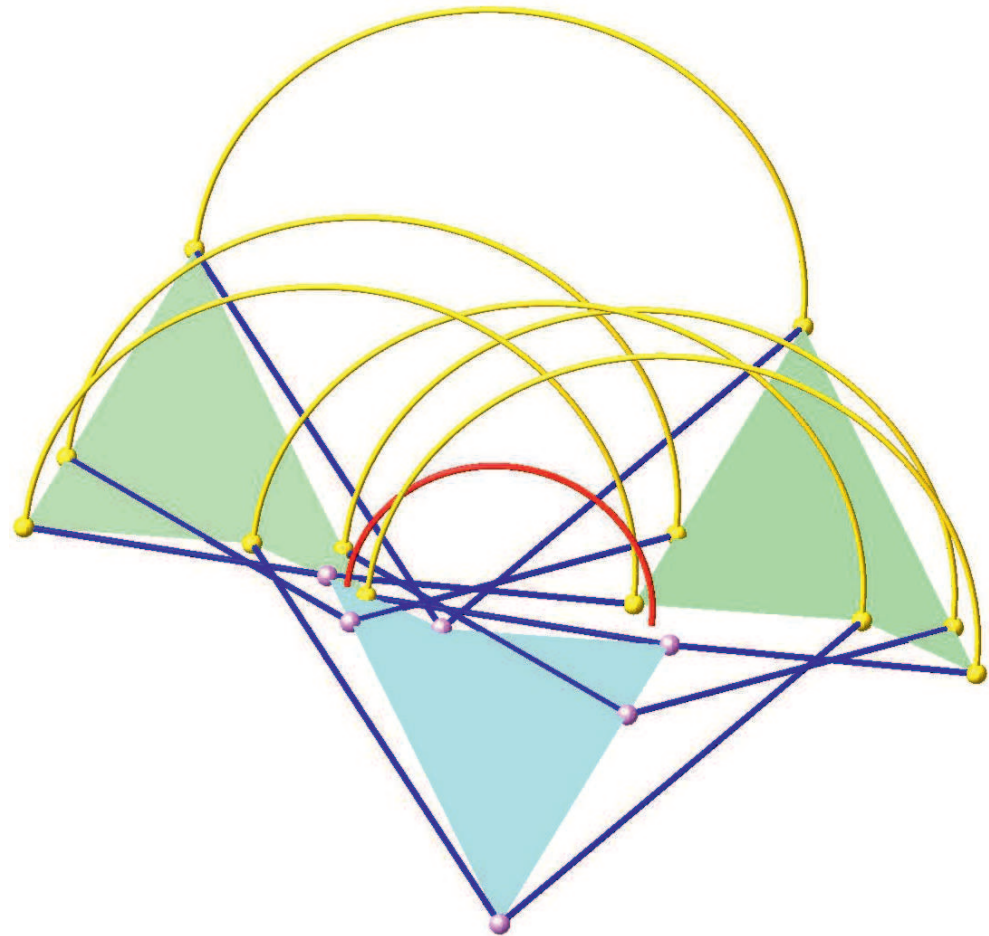
There are two transition poses between this translational self-motion and the 2-parametric line-symmetric self-motion. Again both branching singularities are totally flat configurations.



5. Duporcq Hexapod

This circular translation can also be seen as a point-symmetric motion, where the corresponding curve (half-circle) is illustrated in red.

Note that there is no branching singularity between plane-symmetric self-motions and point-symmetric self-motions.



Conclusion

Summed up one can say, that the Duporcq hexapod is a twofold kinematotropic mechanism, as there are branching singularities between the 2-dimensional line-symmetric self-motion and the 1-dimensional

- point-symmetric self-motion,
- plane-symmetric self-motion.

Due to its kinematotropic behavior and its total flat branching singularities the Duporcq manipulator is possibly of interest for the design of deployable structures.

Acknowledgements

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