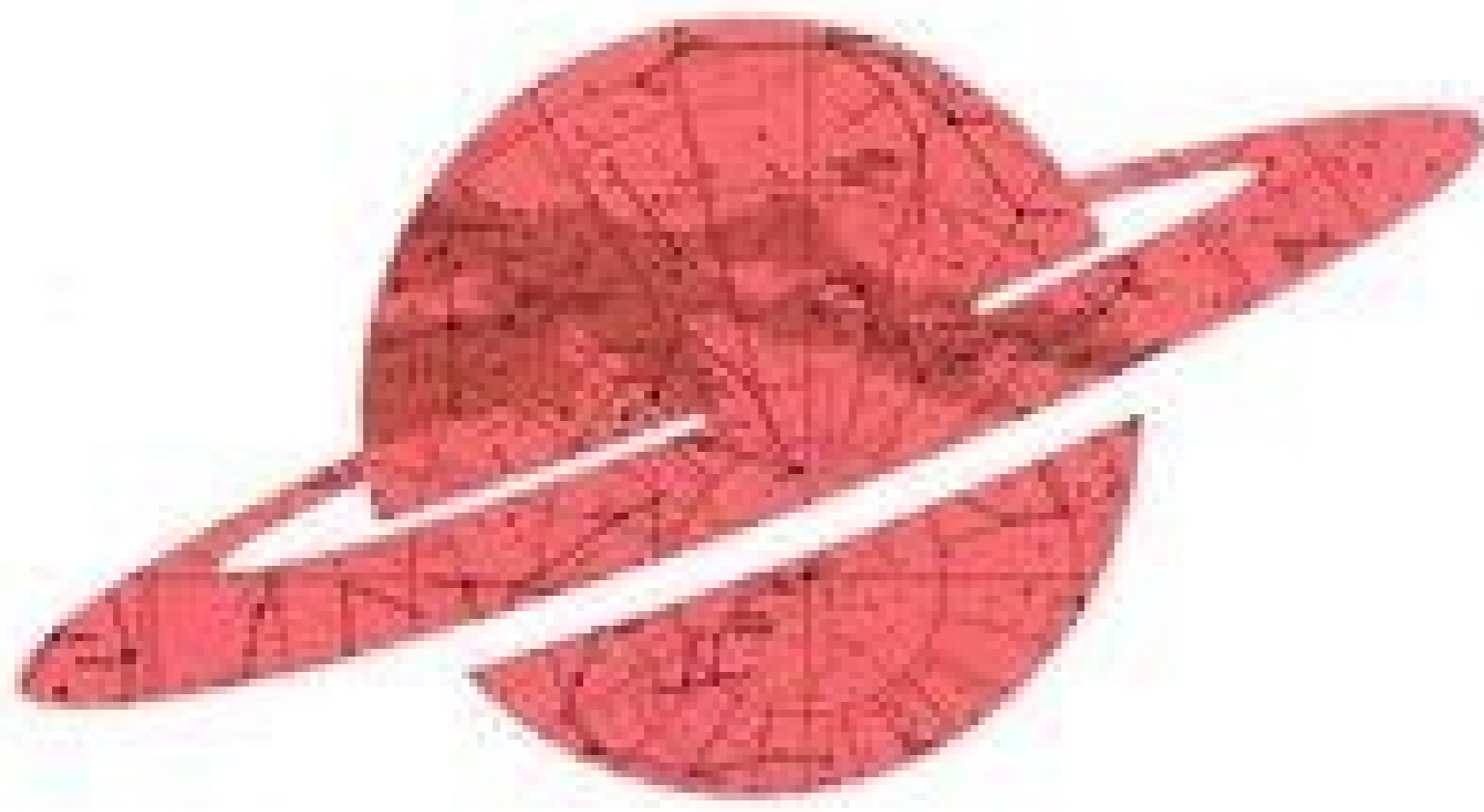
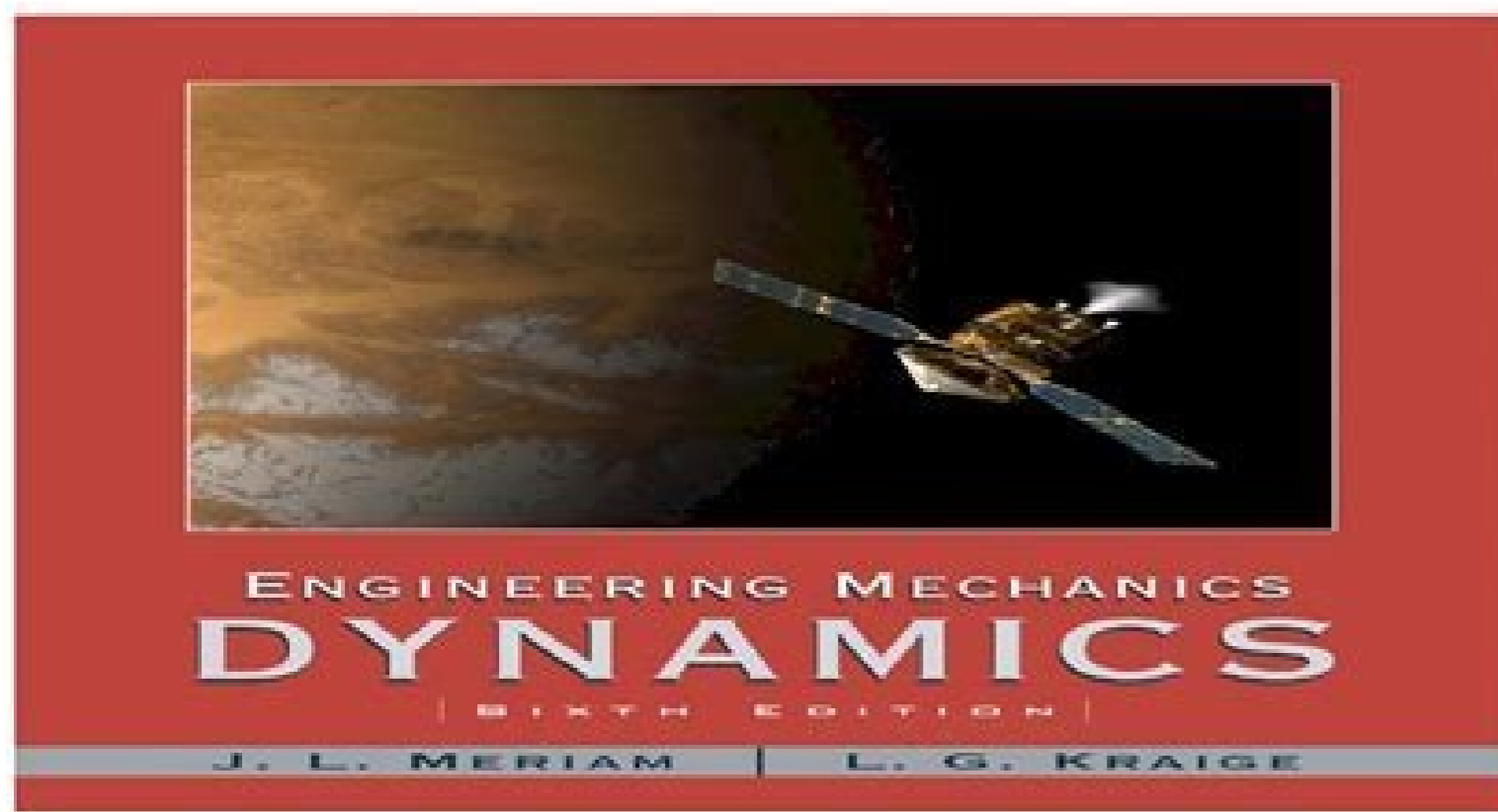
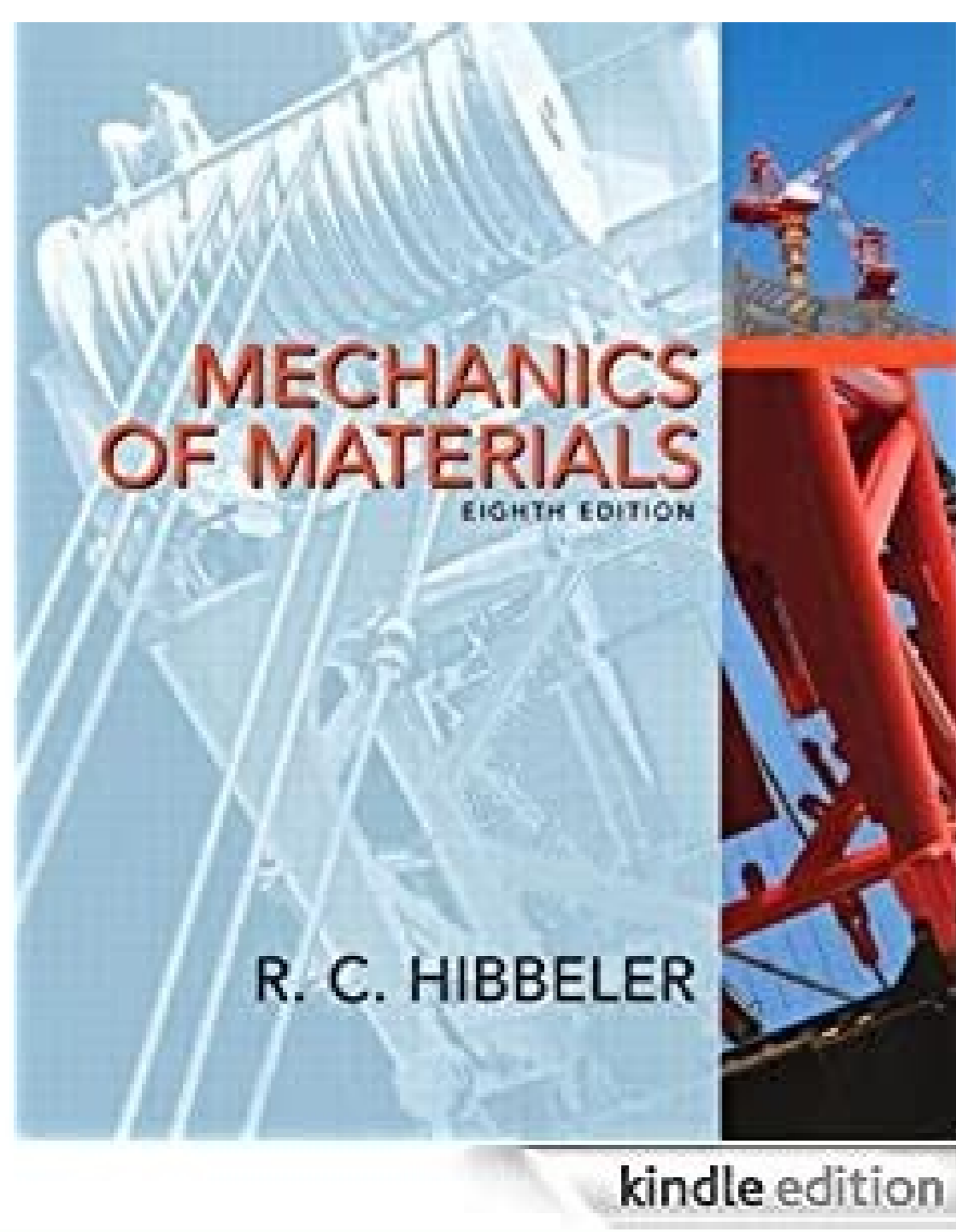


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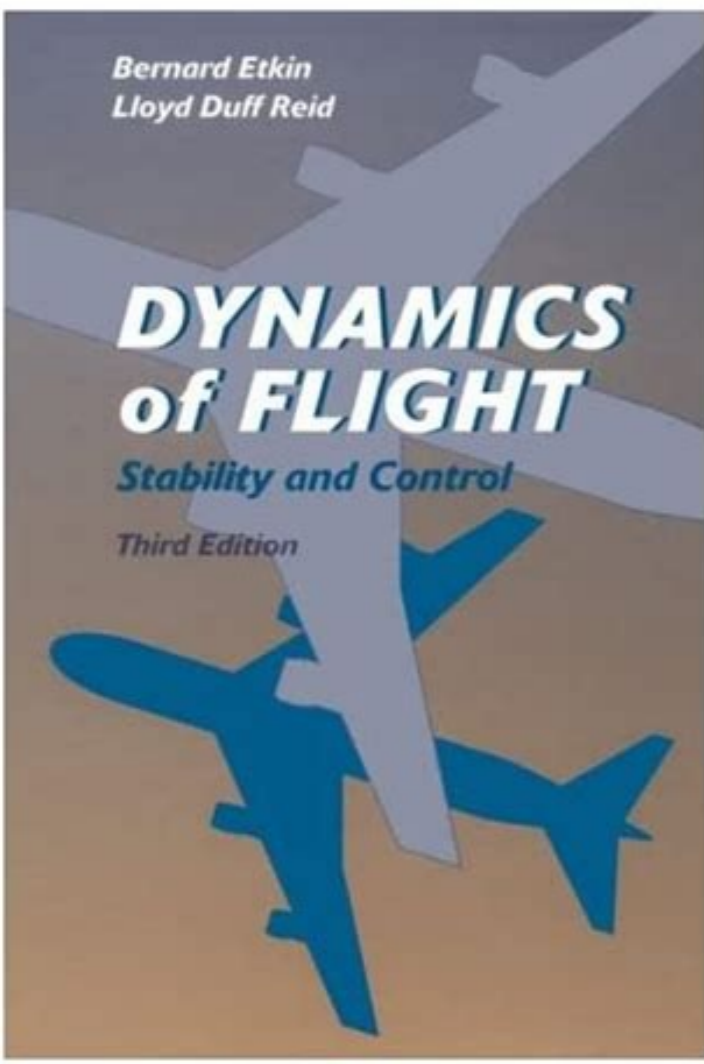
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III



7/2/2011 13.1.1.3 Conversion from implicit to pa...

PLANNING ALGORITHMS

Steven M. LaValle, 2006, Cambridge University Press

Next: 13.1.2 Kinematics for Wheeled Vp 13.1.1.1 Implicit vs. Parametric Previous: 13.1.1.2 Parametric constraints

13.1.1.3 Conversion from implicit to parametric form

There are trade-offs between the implicit and parametric ways to express differential constraints. The implicit representation is more general; however, the parametric form is more useful because it explicitly gives the possible actions. For this reason, it is often desirable to derive a parametric representation from an implicit one. Under very general conditions, it is theoretically possible. As will be explained shortly, this is a result of the implicit function theorem. Unfortunately, the theoretical existence of such a conversion does not help us actually performing the transformation. In many cases, it may not be practical to determine a parametric representation.

To model a mechanical system, it is implicit to express constraints in the implicit form and then derive the parametric representation $\dot{q} = J(q)\dot{u}$. So far there has been no appearance of u in the implicit representation. Since u is interpreted as an action, it needs to be specified while deriving the parametric representation. To understand the issues, it is helpful to first assume that all constraints in implicit form are linear equations in \dot{q} of the form

$$g_1(\dot{q})_1 + g_2(\dot{q})_2 + \dots + g_k(\dot{q})_k = 0, \quad (13.5)$$

which are called Pfaffian constraints. These constraints are linear only under the assumption that q is known. It is helpful in the current discussion to imagine that q is fixed at some known value, which means that each of the $g_i(\dot{q})$ coefficients in (13.5) is a constant.

Suppose that k Pfaffian constraints are given for $k \leq n$ and that they are linearly independent. Recall the standard techniques for solving linear equations. If $k = n$, then a unique solution exists. If $k < n$, then a continuum of solutions exists, which forms an $(n - k)$ -dimensional hyperplane. It is impossible to have

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