Learning goals

- Understand the problems of dealing with rotations
- Understand how to represent rotations
- Understand the terms SO(3) etc.
- Understand the use of the tangent space
- Understand Euler angles, Axis-Angle, and quaternions
- Understand how to interpolate, filter and optimize rotations
Outline

- Rigid transformations
- Problems with rotation matrices
- Properties of rotation matrices
- Matrix groups SO(3), SE(3)
- Manifolds
- Tangent space
- Skew-symmetric matrices
- Exponential map
- Euler angles, angle-axis, quaternions
- Interpolation
- Filtering
- Optimization
Rigid transformations

- Coordinates are related by:
  \[ X_c = RX_w + T \]
  \[
  \begin{bmatrix}
  X_c \\
  1
  \end{bmatrix} =
  \begin{bmatrix}
  R & T \\
  0 & 1
  \end{bmatrix}
  \begin{bmatrix}
  X_w \\
  1
  \end{bmatrix}
  \]

- Rigid transformation belong to the matrix group SE(3)
- What does this mean?
Properties of rotation matrices

Rotation matrix:

\[ R = [r_1, r_2, r_3] \in \mathbb{R}^{3 \times 3} \]

\[ R^T R = I, \det(R) = +1 \]

Coordinates are related by: \( X_c = RX_w \)

- Rotation matrices belong to the matrix group SO(3)
- What does this mean?
Problems with rotation matrices

- Optimization of rotations (bundle adjustment)
  - Newton’s method $x_{n+1} = x_n - \frac{f(x_n)}{f'(x_n)}$

- Linear interpolation

- Filtering and averaging
  - E.g. averaging rotation from IMU or camera pose tracker for AR/VR glasses
Matrix groups

- The set of all the nxn invertible matrices is a group w.r.t. the matrix multiplication:

$$GL(n) = (\{M \in \mathbb{R}^{n \times n} | \det(M) \neq 0\}, \times)$$

General linear group

- Reminder: A group is an algebraic structure consisting of a set of elements equipped with an operation that combines any two elements to form a third element.

- The operation satisfies four conditions called the group axioms, namely closure, associativity, identity and invertibility.

- Closure means for all \( a, b \) in \( G \), the result of the operation, \( a \cdot b \), is also in \( G \).
Matrix groups

- The set of all the $n \times n$ orthogonal matrices is a group w.r.t. the matrix multiplication:

$$O(n) = \left( \{ A \in GL(n) \mid A^{-1} = A^T \}, \times \right)$$

Orthogonal group

$$A \in O(n) \Rightarrow \det(A) = \pm 1$$
Matrix groups

- The set of all the nxn orthogonal matrices with determinant equal to +1 is a group w.r.t. the matrix multiplication:

\[ SO(n) = \{ A \in O(n) | \det(A) = +1 \}, \times \]  

Special orthogonal group

- SO(3) … group of orthogonal 3x3 matrices with det=+1 …. “rotation matrices”

- \[ R_3 = R_1 R_2 \] … R3 is still an SO(3) element
- \[ R_3 = R_1 + R_2 \] … R3 is NOT an SO(3) element. Not a rotation matrix anymore.
Matrix groups

- The set of all the rigid transformations in $\mathbb{R}^n$ is a group (not commutative) with the composition operation

\[
\left( \left\{ F : \mathbb{R}^n \to \mathbb{R}^n \mid F \text{ rigid} \right\} , \circ \right)
\]

- The set is isomorphic to the special Euclidean group $\text{SE}(n)$

- The mathematical properties of a “rigid transformation” are specified by the special Euclidean group $\text{SE}(n)$

\[
RT = \begin{bmatrix} R & T \\ 0 & 1 \end{bmatrix}
\]
Matrix groups: Summary

GL(n) = (\{M ∈ \mathbb{R}^{n×n}| \det(M) ≠ 0\}, ×)  
General linear group

O(n) = (\{A ∈ GL(n)| A^{-1} = A^T\}, ×)  
Orthogonal group

SO(n) = (\{A ∈ O(n)| \det(A) = +1 \}, ×)  
Special orthogonal group

O(n)/SO(n) = (\{A ∈ O(n)| \det(A) = -1 \})  
Set of orthogonal matrices which do not preserve orientation (not a group)

GL(n), O(n), SO(n) and SE(n) are all smooth manifolds (e.g. surfaces, curves, solids immersed in some big vector space)
Special Euclidean group

- The special Euclidean group is constructed by the Cartesian product (a composition operation) from $\text{SO}(n) \times \mathbb{R}^n$.

$$SE(n) = (\text{SO}(n) \times \mathbb{R}^n, \times)$$

$$(M, t) \times (S, q) = (MS, Mq + t)$$

- The Cartesian product defines where the values of $\text{SO}(n)$ and $\mathbb{R}^n$ (rotation and translation) go to form the transformation matrix

$$RT = \begin{bmatrix} R & T \\ 0 & 1 \end{bmatrix}$$

$$SE(3) = \begin{bmatrix} \text{SO}(3) & \mathbb{R}^3 \\ 0 & 1 \end{bmatrix}$$
Manifolds

- Non-mathematical definition: Manifolds are shapes like curves, surfaces, and volumes in Euclidean space (i.e. a vector space)
- A sphere is an example of a manifold of dimension 2.
- The matrix groups SO(3), SE(3) are manifolds.
Shapes of SO(2) and SO(3)

SO(2) \( \rightarrow \) 1-manifold

SO(3) \( \rightarrow \) 3-manifold (3-sphere)
A solid ball in \( \mathbb{R}^3 \)
The tangent space of the manifold $M$ in $p$ (every point $p$ on the manifold has a different tangent space) is isomorphic to a subspace of $V$. 

$$\text{Tangent space of a manifold}$$
Tangent space of a manifold

- $\text{TM}(p)$ is a vector space (subspace of $V$) and has dimension $k$.

- 1-manifold (curves) $\rightarrow$ 1 dim $\text{TM}$ (lines)
- 2-manifold (surface) $\rightarrow$ 2 dim $\text{TM}$ (planes)
- 3-manifold (volumes, e.g. 3-sphere) $\rightarrow$ 3 dim $\text{TM}$ (full volumes)
Tangent space of $\text{SO}(2)$ and $\text{SO}(3)$

$\text{TSO}(2)$ is a vector space with dimension 1
subspace of $\mathbb{R}^{2\times 2}$

subspaces are defined by matrices

$\text{TSO}(3)$ is a vector space with dimension 3
subspace of $\mathbb{R}^{3\times 3}$
Skew-symmetric matrix

- $M$ is skew-symmetric iff $M^T = -M$

$$M^T = -M$$

$$\begin{bmatrix} 0 & 3 & 6 \\ -3 & 0 & -1 \\ -6 & 1 & 0 \end{bmatrix} = \begin{bmatrix} 0 & 4 \\ -4 & 0 \end{bmatrix}$$

$$so(n) = (\{M \in \mathbb{R}^{n \times n} | M^T = -M\}, +, [\,])$$

Special orthogonal Lie algebra

- The term “algebra” means that $so(n)$ is a vector space (more specific than group)
- We have addition in the vector space now (in $SO(n)$ it was only multiplication)
Skew-symmetric matrices

- The special orthogonal Lie algebra is the tangent space of $SO(n)$ at identity.
- The tangent space of $SO(n)$ in any other point $R$ is a rotated version of $so(n)$
- $T_{SO(n)}(R) = R \times so(n)$
- $T_{SO(n)}(I) = so(n)$
so(2) and so(3)

- so(3) is a vector space of dimension 3
- so(2) is a vector space of dimension 1

\[
\begin{bmatrix}
0 & 3 & 6 \\
-3 & 0 & -1 \\
-6 & 1 & 0
\end{bmatrix}
\begin{bmatrix}
0 & 4 \\
-4 & 0
\end{bmatrix}
\]

\(T_{so(2)}\) is a volume

SO(2)
The hat operator

- The hat operator is used to form skew-symmetric matrices
- for so(3):
  \[
  \hat{\cdot} : \mathbb{R}^3 \to \mathfrak{so}(3)
  \]
  \[
  (x, y, z) \rightarrow \begin{bmatrix}
  0 & -z & y \\
  z & 0 & -x \\
  -y & x & 0
  \end{bmatrix}
  \]

- for so(2):
  \[
  \hat{\cdot} : \mathbb{R} \to \mathfrak{so}(2)
  \]
  \[
  \hat{x} \rightarrow \begin{bmatrix}
  0 & -x \\
  x & 0
  \end{bmatrix}
  \]

- Different notation
  \[
  [t]_x = \begin{bmatrix}
  0 & -t_z & t_y \\
  t_z & 0 & -t_x \\
  -t_y & t_x & 0
  \end{bmatrix}
  \]
The hat operator

- The hat operator is used to define the cross-product in matrix form

\[ a \times b = \hat{a}b \quad \forall a, b \in \mathbb{R}^3 \]
Lie groups

- GL(n), O(n), SO(n) and SE(n) are all Lie groups (groups which are a smooth manifold where the operation is a differentiable function between manifolds)
- Also we have seen that the group of skew-symmetric matrices is called Lie algebra so(n) and is the tangent space of the special orthonormal group SO(n)
- But how to compute an element of the tangent space so(n) from SO(n) or vice versa?
- The exponential map!
Exponential map

- Given a Lie group $G$, with its related Lie algebra $g=\mathcal{T}G(I)$, there always exists a smooth map from Lie algebra $g$ to the Lie group $G$ called exponential map

$$exp: g \rightarrow G$$
Exponential map

- Angle-axis representation for rotations:
  \[ \omega \ldots \text{is the angle-axis representation (} \mathbb{R}^3 \text{)} \]
  \[ \exp(\omega) \text{ is the } 3 \times 3 \text{ rotation matrix (element of } SO(3)) \]

\[ \omega \in \mathbb{R}^k \leftrightarrow \exp(\hat{\omega}) \]

\[ \omega \in \mathbb{R}^k \]
\[ \hat{\omega} \in so(n) \]
\[ \exp(\hat{\omega}) = \sum_{k=0}^{\infty} \frac{1}{k!} \hat{\omega}^k \in SO(n) \]
Euler angles

- Euler’s Theorem for rotations: Any element in SO(3) can be described as a sequence of three rotations around the canonical axes, where no successive rotations are about the same axis.

\[
R_x(\alpha) = \begin{bmatrix}
1 & 0 & 0 \\
0 & \cos \alpha & -\sin \alpha \\
0 & \sin \alpha & \cos \alpha
\end{bmatrix}
\]

\[
R_y(\beta) = \begin{bmatrix}
\cos \beta & 0 & \sin \beta \\
0 & 1 & 0 \\
-\sin \beta & 0 & \cos \beta
\end{bmatrix}
\]

\[
R_z(\gamma) = \begin{bmatrix}
\cos \gamma & -\sin \gamma & 0 \\
\sin \gamma & \cos \gamma & 0 \\
0 & 0 & 1
\end{bmatrix}
\]

For any \( R \in SO(3) \) there \( \exists \alpha, \beta, \gamma \mid R = R_x(\alpha)R_y(\beta)R_z(\gamma) \)

\( \alpha, \beta, \gamma \) are called Euler angles of \( R \) according to the XYZ representation (3 DOF/parameters)
Euler angles

- Given \( M \) (element of \( SO(3) \)) there are 12 possible ways to represent it:

  \[
  M \in SO(3) \text{ there } \exists \alpha, \beta, \gamma \mid M = R_x(\alpha)R_y(\beta)R_z(\gamma)
  \]

  \[
  M \in SO(3) \text{ there } \exists \alpha, \beta, \gamma \mid M = R_x(\alpha)R_z(\gamma)R_y(\beta)
  \]

  \[
  M \in SO(3) \text{ there } \exists \alpha, \beta, \gamma \mid M = R_x(\alpha)R_z(\gamma)R_x(\beta)
  \]

  \[
  M \in SO(3) \text{ there } \exists \alpha, \beta, \gamma \mid M = R_z(\alpha)R_x(\gamma)R_z(\beta)
  \]

  ...  

- A common convention is ZYX corresponding to a rotation first around the x-axis (roll), then the y-axis (pitch) and finally around the z-axis (yaw)

[https://en.wikipedia.org/wiki/Aircraft_principal_axes, CC BY-SA 3.0]
Euler angles

- The parameterization has singularities, called gimbal lock.
- A gimbal lock happens when after a rotation around an axis, two axes align, resulting in a loss of one degree of freedom.

![Diagram of Euler angles and gimbal lock](image-url)
Angle-Axis

- Euler’s rotation theorem also states that any rotation can be expressed as a single rotation about some axis.

- The axis can be represented as a three-dimensional unit vector, and the angle by a scalar.
- 3 DOF/parameters
- Angle-axis defines a unique mapping and does not have gimbal lock
Angle-Axis

- The operation to compute the rotation matrix SO(3) from the angle-axis parameters is by using the exponential map!

\[ \omega \in \mathbb{R}^k \rightarrow \exp(\hat{\omega}) \]

- The exponential map can be computed in closed form using the Rodrigues formula

\[ R = I + (\sin \Theta)K + (1 - \cos \Theta)K^2 \]

\[ K = \begin{bmatrix} 0 & -\omega_3 & \omega_2 \\ \omega_3 & 0 & -\omega_1 \\ -\omega_2 & \omega_1 & 0 \end{bmatrix} \]

- There also exists the inverse
Quaternions

- Quaternions are extensions of complex numbers, with 3 imaginary values instead of 1:
  \[ a + ib + jc + kd \]

- Like the imaginary component of complex numbers, squaring the components gives:
  \[ i^2 = j^2 = k^2 = -1 \]

- One way to express a quaternion is as a pair consisting of the real value and the 3D vector consisting of the imaginary components:
  \[ q = (a, w) \text{ with } w = (b, c, d) \]

- It is basically a 4-vector
### Quaternions

- If \( q = a + ib + jc + kd \) is a unit quaternion (\(|q| = 1\)), then \( q \) corresponds to a rotation:

\[
R(q) = \begin{bmatrix}
1 - 2c^2 - 2d^2 & 2bc - 2ad & 2bd + 2ac \\
2bc + 2ad & 1 - 2b^2 - 2d^2 & 2cd - 2ab \\
2bd - 2ac & 2cd + 2ab & 1 - 2b^2 - 2c^2
\end{bmatrix}
\]

- Because \( q \) is a unit quaternion, we can write \( q \) as:

\[
q = \left( \cos \left( \frac{a}{2} \right), \sin \left( \frac{a}{2} \right) w \right), \quad ||w|| = 1
\]

- It turns out the \( q \) corresponds to the rotation whose:
  - Axis of rotation is \( w \) and
  - Angle of the rotation is \( a \)
Interpolation in $\text{SO}(3)$

- Given two rotation matrices $R_1, R_2$ one would like to find a smooth path in $\text{SO}(3)$ connecting these two matrices

$$R(\lambda) \in \text{SO}(3), \lambda \in [0,1]$$

$R(\lambda)$ smooth

$R(0) = R_1$

$R(1) = R_2$
Interpolation in SO(3)

- Approach 1: Linearily interpolate $R_1$ and $R_2$ as matrices (naive approach)

\[
R(\lambda) = \pi_{SO(3)}(\lambda R_1 + (1 - \lambda)R_2)
\]

Projection onto sphere (not accurate)

\[
\pi_{SO(3)}(M) = \arg \min_{R \in SO(3)} \|M - R\|_F^2
\]

Not an element of SO(3), not a rotation matrix at all
Interpolation in SO(3)

- Approach 2: Linearily interpolate $R_1$ and $R_2$ using Euler angles

- Each axis is interpolated independently
- If $R_1$ and $R_2$ are too far apart -> not intuitive motion
Interpolation in SO(3)

- Approach 3: Linearily interpolate $R_1$ and $R_2$ using angle-axis

$$
\omega(\lambda) = \lambda \omega_1 + (1 - \lambda) \omega_2
$$

- Interpolation happens in tangent space (vector space) and is then projected using the exponential map onto the manifold
- A constant speed in the tangent space leads to an increasing speed in the manifold
Interpolation in SO(3)

- Approach 4: Linearily interpolate $R_1$ and $R_2$ using the geodesic distance

- Interpolation happens on manifold, geodesic can be computed using the exponential map
- Method is called SLERP (spherical linear interpolation)
Filtering in SO(3)

- Given \( n \) different noisy measurements for the rotation of an object \( R_1, \ldots, R_n \)

- What is the filtered average of it?
Filtering in SO(3)

- Possible approaches:
  - Average the rotation matrices $R_i$
    \[ \frac{1}{n} \sum_{i=1}^{n} R_i \]
  - Average the Euler angles of each $R_i$
    \[ \left( \frac{1}{n} \sum_{i=1}^{n} \alpha_i, \frac{1}{n} \sum_{i=1}^{n} \beta_i, \frac{1}{n} \sum_{i=1}^{n} \gamma_i \right) \]
  - Average the angle-axis of each $R_i$
    \[ \frac{1}{n} \sum_{i=1}^{n} \omega_i \]
  - Average the quaternions of each $R_i$
    \[ \frac{1}{n} \sum_{i=1}^{n} q_i \]

- All equally problematic and do not accurately respect the noise model

(not rotation)

(is rotation)
Optimization in SO(3)

- Newton-Method
  \[ x_{n+1} = x_n - \frac{f(x_n)}{f'(x_n)} \]

- Naive approach:
  - \( X_n \) are elements of rotation matrix. Then the update step (addition) would not result in a rotation matrix.

- \( X_n \) are Euler angles:
  - To evaluate \( f(X_n) \) the rotation matrix has to be created from the Euler angles. Could lead to gimbal lock.
  - Derivatives of Euler angle construction has to be computed.

- \( X_n \) are elements of the tangent space so(3)
  - Represents angle-axis notation
  - No gimbal lock
  - Minimal representation of 3 parameters
Learning goals - Recap

- Understand the problems of dealing with rotations
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- Understand how to interpolate, filter and optimize rotations