1) Local coordinates for vertices on bodies 2 and 3 are provided below in CW closed boundary chains. Time samples for position and attitude of each body are provided as data in the attached MATLAB code. A sample MATLAB plot of motion for body 2 is shown below.



2) Run the MATLAB code and then modify it to additionally show motion of body 3 on the same MATLAB plot. Manually assess when collision occurs based on the plot and record in the table below. Attach hardcopy of your MATLAB plot and code.

3) Use the bounding circles test to determine when the objects would be candidates for collision detection and record your results below. Attach copy of your code.

4) Use the point-in-polygon test with MATLAB “inpolygon” to detect collision and record your results below. Attach copy of your code.

5) Use the edge intersection test with MATLAB “polyxpoly” to detect collision and record your results below. For example, if edge 4 on body 2 intersects edge 1 on body 3, record E42/E13 . Attach copy of your code.

|  |  |  |  |  |  |  |
| --- | --- | --- | --- | --- | --- | --- |
| **Time** [sec] | 5 | 6 | 7 | 8 | 9 | 10 |
| **Manual**C = collisionblank = no |  |  |  |  |  |  |
| **Bounding circles**C = candidatesblank = no |  |  |  |  |  |  |
| **Point-in-polygon**Which vertices on body 2 are inside polygon 3 ? |  |  |  |  |  |  |
| **Point-in-polygon**Which vertices on body 3 are inside polygon 2 ? |  |  |  |  |  |  |
| **Edge intersection**Which edges on 2 intersect which edges on 3 ? |  |  |  |  |  |  |

**EXTRA CREDIT**

Use Savitsky-Golay interpolants to compute the time for initial collision.



% show\_body2.m - show motion for collision detection

% HJSIII, 19.04.24

clear

% motion data

% time x2 y2 phi2 x3 y3 phi3

% [sec] [in] [in] [rad] [in] [in] [rad]

all = [ 0 0 15.0000 0 0 0 0 ;

 1.0000 5.0000 20.0000 -0.3000 6.6000 0 0.2000 ;

 2.0000 10.0000 24.0000 -0.6000 13.0684 1.3112 0.4000 ;

 3.0000 15.0000 27.0000 -0.9000 19.1474 3.8814 0.6000 ;

 4.0000 20.0000 29.0000 -1.2000 24.5947 7.6080 0.8000 ;

 5.0000 25.0000 30.0000 -1.5000 29.1929 12.3426 1.0000 ;

 6.0000 30.0000 30.0000 -1.8000 32.7589 17.8963 1.2000 ;

 7.0000 35.0000 29.0000 -2.1000 35.1505 24.0477 1.0000 ;

 8.0000 40.0000 27.0000 -2.4000 38.7165 29.6014 0.8000 ;

 9.0000 45.0000 24.0000 -2.7000 43.3147 34.3360 0.6000 ;

 10.0000 50.0000 20.0000 -3.0000 48.7620 38.0626 0.4000 ];

time = all(:,1)'; % size 1 x nt

r2\_all = all(:,2:3)'; % size 2 x nt

phi2\_all = all(:,4)'; % size 1 x nt

ntime = length( time );

% define object 2 in local coordinates

s2p\_poly = [ 2 3 -1 -1 2 ; % local x2p [in]

 3 -1 -2 2 3 ]; % local y2p [in]

rho2 = max( sqrt( diag( s2p\_poly'\*s2p\_poly ) ) ); % maximum radius

[ nr, n2 ] = size( s2p\_poly ); % number of points for body 2

% new figure

figure( 1 )

 clf

% plot origin and outline at each time sample

 for itime = 1 : ntime,

 t = time(itime);

% body 2 = red

 r2 = r2\_all(:,itime); % origin

 phi2 = phi2\_all(itime); % angle

 A2 = [ cos(phi2) -sin(phi2) ; % attitude matrix

 sin(phi2) cos(phi2) ];

 r2\_poly = r2\*ones(1,n2) + A2\*s2p\_poly; % global locations for vertices

 plot( r2(1),r2(2),'ro' ) % plot origin

 axis equal

 hold on

 plot( r2\_poly(1,:), r2\_poly(2,:), 'r' ) % closed curve

 end % bottom - for itime

% bottom - show\_body2.m