Package ‘orientlib’

May 26, 2020

Title Support for Orientation Data
Version 0.10.4
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Description Representations, conversions and display of orientation SO(3) data.
See the orientlib help topic for details.
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License GPL
Depends R (>= 2.13.0), methods, stats
Suggests rgl, scatterplot3d
NeedsCompilation no
Repository CRAN
Date/Publication 2020-05-26 15:20:10 UTC

R topics documented:

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boat3d draws boat glyphs for orientation data

Description

Draws a stylized sailboat to represent an orientation.

Usage

boat3d(orientation, x = 1:length(orientation), y = 0, z = 0, scale = 0.25, col = "red", add = FALSE, box = FALSE, axes = TRUE, graphics = c("rgl", "scatterplot3d"), ...)  

Arguments

- orientation: An orientation object to be shown.
- x, y, z: Coordinates where boats should be shown.
- scale: Size of boats
- col: Colour of boats
- add: Context in which to continue drawing, or FALSE to clear first.
- box: Whether to draw a box around the plot
- axes: Whether to draw axes
- graphics: Which graphics package to use
- ...: Additional graphics parameters; see Details below

Details

For the identity orientation, the sailboats will be shown upright. Other orientations are shown as rotations of this glyph.

The (x,y,z) coordinate appears in the middle of the sail, at the top of the gunwales of the boat.

If the rgl package is installed, it will be used to draw solid faces on the boats which can be moved by the user. If not, but the scatterplot3d package is installed, it will be used to draw fixed wireframe boats. This search order can be changed by modifying the graphics parameter.

Additional graphics parameters may be passed. If scatterplot3d is used, these are passed to the scatterplot3d function (and ignored when adding to an existing plot). Extra parameters are not passed to rgl.

To add to a scatterplot3d plot, you must pass the return value from the initial plot as the value of add. See the orientlm function for an example.
Value

A current plot number for rgl, or a scatterplot3d drawing context. In any case, an attribute named graphics is added to indicate the drawing device type.

Note

Requires the rgl or scatterplot3d package.

Author(s)

Duncan Murdoch

Examples

x <- eulerzyx(psi=c(0,pi/4,0,0), theta=c(0,0,pi/4,0), phi=c(0,0,0,pi/4))

# Need a 3D renderer; assume scatterplot3d, but others could be used
s <- boat3d(x, 0:3, axes = FALSE, graphics = 'scatterplot3d')
text(s$xyz.convert(0:3, rep(-0.5,4), rep(-0.5,4)),
     label = c('Id','z','y','x'))

## Not run:
# if the rgl package is loaded, this code will work
boat3d(x, 0:3, axes = FALSE, graphics = 'rgl')
rgl.bbox(xat=0:3,xlab=c('Id','z','y','x'),yat=1,zat=1,color='grey')

## End(Not run)
Create an orientation using Euler angles

Description

Create an eulerzxz-class object.

Usage

eulerzxz(phi, theta, psi)

Arguments

phi Rotation about Z axis
theta Rotation about X axis
psi Further rotation about Z axis

Details

The rotations are expressed in radians and applied in the order Z, X, Z.

If theta and psi are missing, phi is taken to be an n x 3 matrix (or 3 element vector) holding all 3 Euler angles; alternatively, it may be an orientation object.

Value

An eulerzxz-class object.

Author(s)

Duncan Murdoch

See Also

eulerzxz-class, eulerzyx-class, rotmatrix, rotvector, quaternion, skewvector, skewmatrix

Examples

```r
x <- eulerzxz(c(1,0,0), c(0,1,0), c(0,0,1))
x
rotmatrix(x)
```
Create an orientation using Euler angles

Description

Creates an eulerzyx-class object.

Usage

eulerzyx(psi, theta, phi)

Arguments

psi Rotation about Z axis
theta Rotation about Y axis
phi Rotation about X axis

Details

The rotations are expressed in radians and applied in the order Z, Y, X.
If theta and phi are missing, psi is taken to be an n x 3 matrix (or 3 element vector) holding all 3 Euler angles; alternatively, any orientation object may be used.

Value

An eulerzyx-class object.

Author(s)

Duncan Murdoch

See Also

eulerzyx-class, rotmatrix, rotvector, quaternion, skewvector, skewmatrix

Examples

x <- eulerzyx(c(1,0,0), c(0,1,0), c(0,0,1))
x rotmatrix(x)
Methods for indexing orientations

Description

Methods are defined for indexing all types of orientations.

Details

Single bracket indexing (e.g. x[1:3]) creates a new orientation object of the same class as the original by selecting the appropriate entries. Double bracket indexing (e.g. x[[3]]) extracts the chosen data as a matrix or vector, depending on the class of the orientation.

Length of orientation object

Description

The generic length() function has methods for orientations; it counts the number of orientations in the object.

Matrix orientation classes

Description

An orientation represented by 3 x 3 SO(3) matrices or 3 x 3 skew symmetric matrices.

Objects from the Class

Objects can be created by calls of the form rotmatrix(x) or skewmatrix(x). The objects store the matrices in a 3 x 3 x n array.

Slots

x: 3 x 3 x n array holding the matrices.

Extends

Class "orientation", directly. Class "vector", by class "orientation".
Methods

[,<-  Extract or assign to subvector
[, [[<- Extract or assign to an entry
length  The length of the orientation vector
coerce  Coerce methods are defined to convert all orientation descendants from one to another, and to coerce an appropriately shaped matrix or array to a rotmatrix

Author(s)
Duncan Murdoch

See Also
orientation-class, vector-classes, rotmatrix, skewmatrix

Examples

x <- rotmatrix(matrix(c(1,0,0, 0,1,0, 0,0,1), 3, 3))
x
skewmatrix(x)

Description

Methods are defined for matrix multiplication %*%, transposition t(), and real powers ^. These operate on the orientations term by term.

mean-methods

Methods for calculating the mean

Description

The mean function.

Methods

x = "ANY"  the standard mean function
x = "orientation" find the nearest SO(3) matrix to the mean rotmatrix-class representation of the orientations
nearest

Find nearest SO(3) or orthogonal matrix.

Description
Converting arbitrary 3 x 3 matrices into the nearest SO(3) or orthogonal matrix.

Usage
nearest.SO3(x)
nearest.orthog(x)

Arguments
x

3 x 3 matrices stored in a 3 x 3 x n array)

Details
Uses Stephens’ (1979) algorithm to find the nearest (in entry-wise Euclidean sense) SO(3) or orthogonal matrix to a given matrix.

Value
nearest.SO3 produces an orientation-class object holding the closest orientations.
nearest.orthog produces a 3 x 3 x n array of orthogonal matrices.

Author(s)
Duncan Murdoch

References

See Also
orientation-class

Examples
x <- matrix(rnorm(9), 3,3)
nearest.orthog(x)
nearest.SO3(x)
x <- -x
nearest.orthog(x)
nearest.SO3(x)
**orientation-class**

Class "orientation"

**Description**

Abstract class for vectors of various representations of SO(3) (orientation) objects.

**Objects from the Class**

A virtual Class: No objects may be created from it.

**Methods**

- **coerce**
  Methods are defined to coerce orientation objects to any concrete descendant class.

- `%*%`
  Matrix multiplication acts on orientation objects component by component, producing compositions of the rotations.

- `^`
  An orientation is raised to a power by multiplying its component rotation angles by that power.

- `t`
  The transpose of an orientation object is its component by component inverse.

- **mean**
  The mean of an orientation object is the nearest SO(3) matrix to the element-by-element mean of its 3 x 3 rotation matrix representation.

- **weighted.mean**
  The weighted mean, defined analogously to the mean.

**Author(s)**

Duncan Murdoch

**See Also**

matrix-classes, vector-classes

**Examples**

```r
x <- rotmatrix(diag(3))
x
rotvector(x)
eulerzyx(x)
eulerzxz(x)
quaternion(x)
```
orientlib

**Orientation Library**

**Description**

Representations, conversions and display of orientation data.

**Details**

This package contains methods for working with orientation data, i.e. data from SO(3). The basic abstract class is the `orientation`; there are several concrete classes (`rotmatrix`, `rotvector`, `eulerzyx`, `eulerzxz`, `quaternion`, `skewmatrix` and `skewvector`) storing different representations of orientations.

Methods are defined to get the length of a vector of orientations, as well as to extract and replace elements, and to multiply orientations and raise them to real powers.

There are also utility functions `rotation.distance`, `rotation.angle`, `nearest.orthog`, `nearest.SO3`.

There is a plotting method `boat3d` to display orientation data in a 3D plot, and a linear modelling function `orientlm`.

**Release History**

- Version 0.9
  - Added CITATION file, dropped djmrgl support.
- Versions 0.3 to 0.8
  - Changes for CRAN compliance and minor corrections.
- Version 0.2
  - Added `mean` and `weighted.mean`.
  - Made `orientation` descend from `vector`.
  - Added `[[` methods.
  - Changed default look of boats.
  - Made `rotmatrix` etc. into conversion functions between orientation types.
  - Added `eulerzxz` class.
  - Added various parameters to `boat3d`.
  - Added `orientlm` regression function plus transpose `t()` method.
  - Added `rgl` and `scatterplot3d` support to `boat3d` function.
  - Added `skewmatrix`.
- Version 0.1
  - First release.

**Note**

Plots require either the `rgl` or `scatterplot3d` package.
orientlm

Author(s)

Duncan Murdoch

orientlm  *Linear models for orientation data*

Description

Regression models for matched pairs of orientations.

Usage

orientlm(observed, leftformula, trueorient = rotmatrix(diag(3)),
          rightformula, data = list(), subset, weights, na.action,
          iterations = 5)

Arguments

- **observed**: Observed orientations
- **leftformula**: Formula for “left” model (see below)
- **trueorient**: “True” orientation (see below)
- **rightformula**: Formula for “right” model (see below)
- **data**: Optional data frame for predictors in linear model
- **subset**: Optional logical vector indicating subset of data
- **weights**: Optional weights
- **na.action**: Optional NA function for predictors
- **iterations**: How many iterations to use. Ignored unless both leftformula and rightformula are specified.

Details

The Prentice (1989) model for matched pairs of orientations was

\[ E(V_i) = kA_1^T U_i A_2 \]

where \( V_i \) is the observed orientation, \( A_1 \) and \( A_2 \) are orientation matrices, and \( U_i \) is the “true” orientation, and \( k \) is a constant. It was assumed that errors were symmetrically distributed about the identity matrix.

This function generalizes this model, allowing \( A_1 \) and \( A_2 \) to depend on regressor variables through leftformula and rightformula respectively. These formulas should include the predictor variables (right hand side) only, e.g. use \( \sim x + y + z \) rather than \( response \sim x + y + z \). Specify the response using the observed argument. If both formulas are \( \sim 1 \), i.e. intercepts only, then Prentice’s original model is recovered. More general models are fit by coordinatewise linear regression.
in the \texttt{rotmatrix} representation of the orientation, with fitted values projected onto SO(3) using the \texttt{nearest.SO3} function.

When both left and right models are given, Prentice’s iterative approach is used with a fixed number of iterations. Note that Shin (1999) found that Prentice’s scheme sometimes fails to find the global minimum; this function presumably suffers from the same failing.

\textbf{Value}

Returns a list containing the following components:

\begin{itemize}
\item \texttt{leftfit} Result of \texttt{lm} call based on \texttt{leftformula}
\item \texttt{rightfit} Result of \texttt{lm} call based on \texttt{rightformula}
\item \texttt{A1} Fitted values of $A_1$ for each observation
\item \texttt{A2} Fitted values of $A_2$ for each observation
\item \texttt{predict} Fitted values of $A_1^t U_i A_2$ for each observation
\end{itemize}

\textbf{Author(s)}

Duncan Murdoch

\textbf{References}


\textbf{Examples}

\begin{verbatim}
x <- rep(1:10,10)
y <- rep(1:10,each=10)
A1 <- skewvector(cbind(x/10,y/10,rep(0,100)))
A2 <- skewvector(c(1,1,1))
trueorientation <- skewvector(matrix(rnorm(300),100))
oNoise <- skewvector(matrix(rnorm(300)),100))
obs <- t(A1) %*% trueorientation %*% A2 %*% noise

fit <- orientlm(oobs, ~ x + y, trueorientation, ~ 1)

context <- boat3d(A1, x, z=y, col = 'green', graphics='scatterplot3d')
boat3d(fit$A1, x, z=y, add=context)
\end{verbatim}
Create an orientation using quaternions

Description

Creates a quaternions object.

Usage

quaternion(m)

Arguments

m n x 4 matrix or 4 element vector containing a unit quaternion, or an orientation object

Details

The rows of m are 4 element unit vectors interpreted as follows: the first 3 \((x,y,z)\) define the axis of rotation, and the last element gives the cosine of half the angle of rotation in a counter-clockwise direction when looking down the axis towards the origin.

Value

A quaternions object.

Author(s)

Duncan Murdoch

See Also

quaternions, rotmatrix, rotvector, eulerzyx, eulerzxx, skewvector, skewmatrix

Examples

```r
x <- quaternion(c(1,0,0,0))
x
rotmatrix(x)
```
rotation.distance  

Rotation angle or distance

**Description**

Calculates the angle (in radians) of the rotation taking one orientation to another.

**Usage**

rotation.angle(x)
rotation.distance(x, y)

**Arguments**

x, y  
Two orientation objects

**Details**

If y is missing in a call to rotation.distance, it is treated as the identity, i.e. rotation.angle(x) is calculated.

**Value**

rotation.distance returns a vector of length max(length(x), length(y)) containing the angle of the rotation taking corresponding elements of x to y (with the usual recycling rules if they are different lengths).

rotation.angle is equivalent to calculating the rotation.distance to the identity matrix.

**Author(s)**

Duncan Murdoch

**See Also**

orientation-class, rotation.angle

**Examples**

rotation.angle(eulerzyx(1,0,0))
rotation.distance(eulerzyx(1,0,0), eulerzyx(0,1,0))
rotmatrix

Create an orientation using Euler angles

Description

Creates a rotmatrix-class object.

Usage

rotmatrix(a)

Arguments

a

A 3 x 3 matrix or 3 x 3 x n array of matrices or an orientation object.

Value

A rotmatrix-class object.

Author(s)

Duncan Murdoch

See Also

rotmatrix-class, rotvector, eulerzyx, eulerzxz, quaternion, skewvector, skewmatrix

Examples

x <- rotmatrix(matrix(c(1,0,0, 0,1,0, 0,0,1), 3, 3))
x

rotvector

Create an orientation using vectorized 3x3 matrices

Description

Creates a rotvector-class object.

Usage

rotvector(m)

Arguments

m

n x 9 matrix or 9 element vector whose rows are vectorized 3x3 matrices, or an orientation object.
skewmatrix

Details
Converts a matrix whose rows are vectorized 3x3 matrices (in column-major form) into an \texttt{rotvector-class} object.

Value
A \texttt{rotvector-class} object.

Author(s)
Duncan Murdoch

See Also
\texttt{rotvector-class}, \texttt{rotmatrix}, \texttt{eulerzyx}, \texttt{eulerzxz}, \texttt{quaternion}, \texttt{skewvector}, \texttt{skewmatrix}

Examples
\begin{verbatim}
x <- rotvector(c(0,1,0,-1,0,0,0,0,1))
x
rotmatrix(x)
\end{verbatim}

\begin{verbatim}
skewmatrix
\end{verbatim}
Create an orientation using the entries in a skew-symmetric matrix representation

Description
Creates a \texttt{skewmatrix-class} object.

Usage
\texttt{skewmatrix(a)}

Arguments
\begin{verbatim}
a 3 x 3 x n array or 3 x 3 matrix containing the entries of a skew-symmetric matrix, or an orientation object.
\end{verbatim}

Details
The entries \texttt{a[,i]} are 3 x 3 skew-symmetric matrices. The matrix exponential of these give SO(3) matrices.

Value
A \texttt{skewmatrix-class} object.
**skewvector**

**Author(s)**
Duncan Murdoch

**See Also**

`skewvector-class, skewvector, rotmatrix, rotvector, eulerzyx, eulerzxz, quaternion`

**Examples**

```r
x <- skewmatrix(matrix(c(0,1,2,-1,0,3,-2,-3,0),3,3))
x
rotmatrix(x)
skewvector(x)
rotation.angle(x)
```

---

**Description**

Creates a `skewvector-class` object.

**Usage**

```r
skewvector(m)
```

**Arguments**

- `m` n x 3 matrix or 3 element vector containing a the entries of a skew-symmetric matrix, or an orientation object.

**Details**

The rows of `m` are 3 element vectors `(x, y, z)` interpreted as follows: the matrix exponential of the matrix `((0, -z, y), (z, 0, -x), (-y, x, 0))` is the SO(3) matrix.

**Value**

A `skewvector-class` object.

**Author(s)**
Duncan Murdoch

**See Also**

`skewvector-class, skewmatrix, rotmatrix, rotvector, eulerzyx, eulerzxz, quaternion`
Examples

```r
x <- skewvector(c(1,0,0))
x
rotmatrix(x)
rotation.angle(x)
```

Description

An vector of orientations, each represented by a vector of numbers. Each of these types stores orientations as rows of a matrix in slot `x`.

The `eulerzyx` class uses 3 Euler angles in the roll-pitch-yaw scheme (rotation about Z axis, then Y axis, then X axis).

The `eulerzxz` class uses 3 Euler angles in the X system scheme (rotation about Z axis, then X axis, then Z axis again).

The `rotvector` class uses the 9 components of a 3 x 3 rotation matrix, stored in column-major order.

The `quaternion` class uses the 4 components of a unit quaternion.

The `skewvector` class uses the 3 non-zero components of a skew-symmetric matrix, where \((x,y,z)\) stores the matrix \(((0,-z,y),(z,0,-x),(-y,x,0))\).

Objects from the Class

Objects of each class can be created by calls to the corresponding constructor functions: `eulerzyx`, `eulerzxz`, `rotvector`, `quaternion`, `skewmatrix` and `skewvector`.

Slots

- `x`: An \(n \times m\) matrix object holding the vector representations, where \(m\) is 3, 4, or 9.

Extends

Class "orientation", directly. Class "vector", by class "orientation".

Methods

- `[`, `<-`: Extract or assign to subvector
- `[`, `[[<-`: Extract or assign to an entry
- `length`: The length of the orientation vector
- `coerce`: Coerce methods are defined to convert all `orientation` descendants from one to another, and to coerce an appropriately shaped matrix or array to a `rotmatrix`
Author(s)
Duncan Murdoch

See Also
Constructor and coercion functions rotmatrix, eulerzyx, eulerzxz, rotvector, quaternion, and skewvector.
Classes matrix-classes, orientation-class.

Examples
x <- eulerzyx(0,pi/4,0)
x
eulerzxz(x)
rotmatrix(x)
rotvector(x)
quaternion(x)
skewvector(x)

Description
The weighted mean function.

Details
The weighted mean for orientations is the nearest SO(3) matrix to the entrywise weighted mean of the rotmatrix-class matrices.

Methods
x = "ANY", w = "ANY" the standard stats::weighted.mean
x = "orientation", w = "numeric" weighted mean for orientations
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