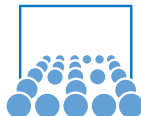


# PSE Game Physics

## Session (7) Friction

Oliver Meister, Sebastian Rettenberger, Roland Wittmann

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# Outline

## Friction types

- Static friction

- Dynamic friction

- Some coefficients

## Friction as impulses

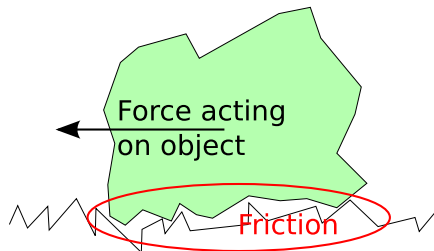
- Change of velocity due to friction

- The modified velocity resolution algorithm

# Friction

- A **force** generated when one object moves or tries to move in contact with another object.
- Two types of friction: **static** and **dynamic** friction.
- Results into **resistance** at the point of contact to the current motion.

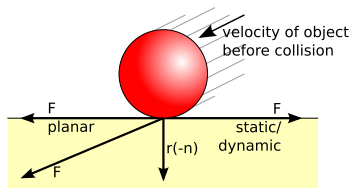
# Static friction - Part 1



**Figure:** Example for static friction between an object and a surface

Object is not moving since force created by static friction stops it from moving.

## Static friction - Part 2



**Figure:** Example for static friction between sphere and plane

- The **reaction force**  $r$  is calculated:

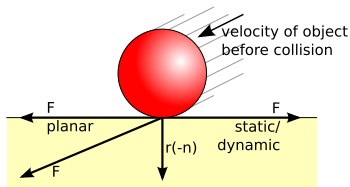
$$r = -\vec{f} \cdot \vec{n},$$

with  $f$  being the force acting between both objects.

- Static friction force depends on the material at the point of contact (the coefficient  $\mu$ ) and the reaction force  $r$ :

$$|\vec{f}_{static}| \leq \mu_{static} r$$

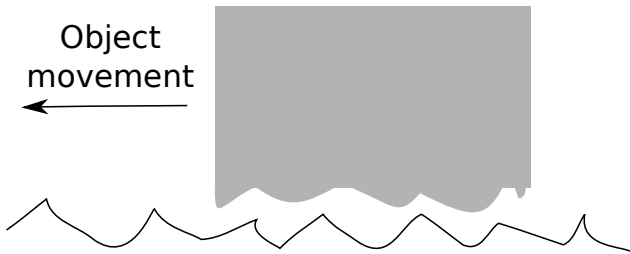
# Static friction - Part 3



**Figure:** Example for static friction between sphere and plane

- $\mu_{static}$  an empirical property described in tables for different pairs of materials.
- Compute  $\vec{f}_{planar}$ , e. g. using  $\vec{f}_{planar} = \vec{f} + |\vec{r}|\vec{n}$
- If a static friction is detected ( $|\vec{f}_{planar}| \leq \mu_{static}|\vec{r}|$ ), use  $\vec{f}_{static} = -\vec{f}_{planar}$

# Dynamic friction - Part 1



**Figure:** Example for static friction between an object and a surface

- Has similar behaviour as the static friction.
- Described through different friction coefficient  $\mu_{dynamic}$ .
- Applied, once the static friction force is exceeded.

## Dynamic friction - Part 2

- The equation for the dynamic friction depends on the dynamic friction coefficient  $\mu_{dynamic}$  as well as the reaction force  $\vec{r}$ :

$$|\vec{f}_{dynamic}| = -\mu_{dynamic}|\vec{r}|$$

- Be aware, that this force acts parallel to the planar force!



# Some coefficients

Materials	Static friction	Dynamic friction
Wood on stone	0.7	0.3
steel on steel	0.16	0.12

# Outline

## Friction types

Static friction

Dynamic friction

Some coefficients

## Friction as impulses

Change of velocity due to friction

The modified velocity resolution algorithm

# How to implement friction?

- **Impulse-based** engine.
- We compute the changes of the velocities due to acting impulses.
- Reaction forces are not computed.
- The standard friction-theory cannot be applied directly.

# Friction Properties

Friction Properties:

## Static friction:

- Keeps the velocity of the object at zero on contact plane.
- Velocity in the direction of the contact normal already adjusted.
- Modify the velocity in the two other directions on the contact plane.

## Dynamic friction:

- Scale the the planar velocity  $v_{planar}$  with  $\mu_{dynamic}$ .

# Friction as impulses

- What does the friction do in terms of impulses and velocities?

$$\Delta \vec{v} = \Delta \vec{v} - \begin{cases} \vec{v}_{planar} & \text{if } \|\vec{v}_{planar}\| \leq v_c \cdot \mu_{static} \\ \mu_{dynamic} \cdot \vec{v}_{planar} & \text{else} \end{cases}$$

- Here we approximate the dynamic change of velocity using the planar velocity instead of the closing velocity directly.
- We can compute  $\vec{v}_{planar}$  as :

$$\vec{v}_{planar} = \vec{v}_{collision} - v_c \cdot \vec{n}$$

with  $\vec{v}_{collision} = \vec{v}_A - \vec{v}_B$  as defined on slide 16 in presentation slides of session 6.

# Angular motion to velocity

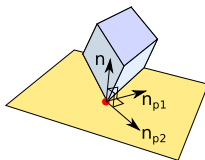
## Without friction:

1. Compute the **torque per unit impulse** in the direction of the contact normal.
2. Convert the **torque to rotation** using the inertia tensor.
3. Convert the **rotation to linear velocity** for the current contact point.
4. Convert the **velocity** back into **contact coordinates**

Finally we have the change of velocity per unit impulse aligned at collision normal.

## With friction:

- Change the algorithm so that all **three directions of the contact are considered**.
- Use the basis matrix  $B$  instead of contact normal.
- Our new task: Compute the impulse  $g_\mu$  which has to be applied to gain the desired change of velocity for handling
  1. angular momentum
  2. friction forces



**Figure:** Friction collision basis

## The skew-symmetric matrix

In the case of friction we should change the Impulse algorithm to use all three directions of the contact (one direction is the contact normal and the other two are defined as the contact plane). We need to replace the contact normal with a matrix - the skew matrix.

- Consider  $\vec{v} \times \vec{w}$  with  $\vec{v} = \begin{bmatrix} a \\ b \\ c \end{bmatrix}$ .
- Using the skew matrix, we can rewrite this equation to

$$\vec{v} \times \vec{w} = \begin{bmatrix} 0 & -c & b \\ c & 0 & -a \\ -b & a & 0 \end{bmatrix} \vec{w}$$

- Keep in mind that  $\vec{v} \times \vec{w} = -\vec{w} \times \vec{v}$  in case that the skew matrix of  $\vec{w}$  is already computed!
- We will use the following notation for the skew matrix:  
 $S_{\vec{v}}$  - the skew matrix for the vector  $\vec{v}$ .



# The algorithm for linear motion

Question: How to handle scalar values?

1. Consider the following equation:

$$\vec{g}_\mu = m \cdot \Delta \vec{v}_l \Rightarrow \Delta \vec{v}_l = m^{-1} \cdot \vec{g}_\mu$$

2. Express the inverse mass as matrix to be added to the angular matrix:

$$\begin{bmatrix} m^{-1} & 0 & 0 \\ 0 & m^{-1} & 0 \\ 0 & 0 & m^{-1} \end{bmatrix}$$

## The algorithm for angular motion (1/2)

1. Compute the change of impulsive torque  $\Delta \mathbf{U}$  for each object when applying unit impulses:

$$\Delta \mathbf{U} = \mathbf{X} \cdot \mathbf{N}$$

with  $\mathbf{X}$  representing the lever arm equal to  $\mathbf{S}_{\vec{p}_{contact}}$  with  $\vec{p}_{contact}$  the relative contact position (in each object space).  $\mathbf{N}$  represents the orthonormal basis for the collision space with one axis representing the collision normal.

2. Compute the change in angular velocity: torque vector transformed by the tensor matrix. In this case we have a simple matrix-multiplication:

$$\Delta \mathbf{V}_r = \mathbf{M}^{-T} \mathbf{I}^{-1} \mathbf{M}^T \Delta \mathbf{U}$$

(Hint: Compare this with the formulae for the angular momentum!)

## The algorithm for angular motion (2/2)

4. Compute the linear velocity change  $\Delta \mathbf{V}$  per unit impulses at collision point.

$$\Delta \mathbf{V} = \Delta \mathbf{V}_r \mathbf{X} + \Delta \mathbf{V}_l$$

5. Convert velocity from collision coordinates into world coordinates:

$$\Delta \mathbf{V}_{\text{contact}} = \mathbf{N}^{-1} \Delta \mathbf{V}$$

6. Finally, impulses have to be applied to fit our friction model (e. g. removing all planar velocity changes for static friction). This leads to the following system of equations with  $\vec{v}_{\text{change}}$  representing the desired change in velocity in collision space and  $\vec{p}$  the desired impulse to be applied:

$$(\Delta \mathbf{V}_{\text{contact}}) (\vec{p}) = (\vec{v}_{\text{change}})$$