Quaternion Applications

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Siggraph Asia 2012 Tutorial

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OUTLINE

I: (55 min) **Introduction to Quaternions:**

What are they good for?

Understanding Rotation Sequences!

II a: (15 min) **Quaternion Tubing:**

Visualizing Framed Space Curves

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...OUTLINE...

II b: (15 min) **Quaternion Protein Maps:**

Amino Acid Frame Sequences with Quaternions

II c: (20 min) **Intro to Dual Quaternions:**

Applications to Six-Degrees-of-Freedom

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Part I

Introduction to Quaternions:

...Twisting Belts and Rolling Balls...

Explaining Rotation Sequences with Quaternions

4

Where Did Quaternions Come From?

. . . from the discovery of *Complex Numbers:*

- $\boxed{z = x + iy}$ Complex numbers = realization that $z^2 + 1 = 0$ cannot be solved unless you have an “imaginary” number with $i^2 = -1$.
- **Euler’s formula**: $e^{i\theta} = \cos\theta + i\sin\theta$ allows you to do most of 2D geometry.

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Hamilton

The first to ask *“If you can do 2D geometry with complex numbers, how might you do 3D geometry?”* was William Rowan Hamilton, circa 1840.

Sir William Rowan Hamilton
4 August 1805 — 2 September 1865

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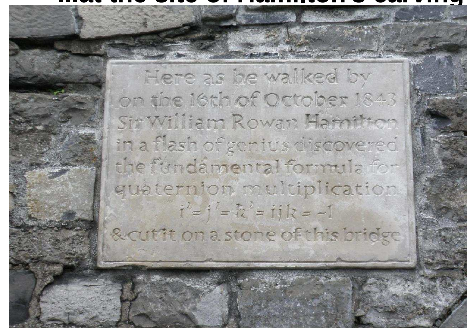
Hamilton's epiphany: 16 October 1843

"An electric circuit seemed to close; and a spark flashed forth . . . Nor could I resist the impulse – unphilosophical as it may have been – to cut with a knife on a stone of Brougham Bridge, as we passed it, the fundamental formula with the symbols, i, j, k; namely,

$$i^2 = j^2 = k^2 = ijk = -1$$

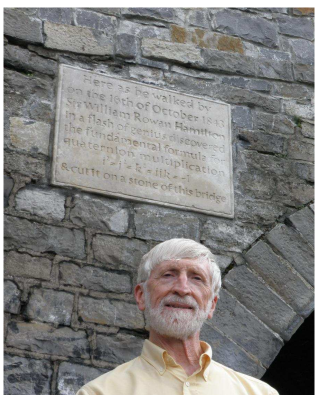
which contains the Solution of the Problem..."

...at the site of Hamilton's carving



The plaque on Broome Bridge in Dublin, Ireland, commemorating the legendary location where Hamilton conceived of the idea of quaternions. *(Photo taken July 2012)*.

...the author on Broome Bridge...



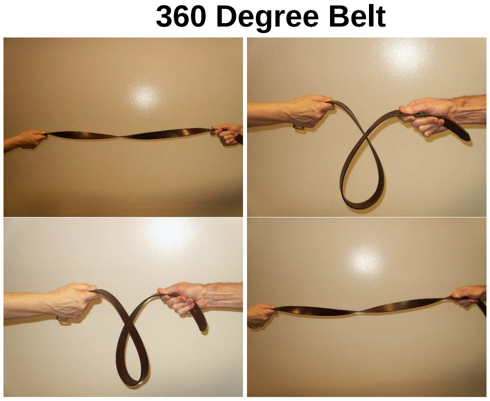
Yes, I have actually been there!

The Belt Trick

Quaternion Geometry in our daily lives

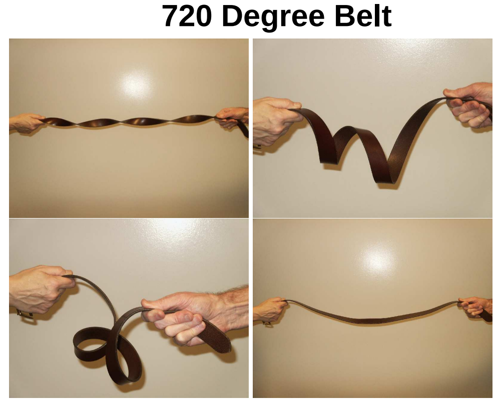
- Two people hold ends of a belt.
- Twist the belt either 360 degrees or 720 degrees.
- **Rule:** *Move belt ends any way you like but do not change orientation of either end.*
- Try to straighten out the belt.

360 Degree Belt



360 twist: stays twisted, can change DIRECTION!

720 Degree Belt



720 twist: CAN FLATTEN OUT WHOLE BELT!

The Beltless Trick

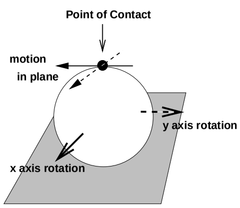
Quaternion Geometry is right in your hand!

- Hold a coffee cup (empty is a good idea) in the palm of your hand.
- Keeping the cup vertical, user your hand to twist the handle, first by 360 degrees (painful).
- *Now CONTINUE another 360 degrees,* for a total of 720 degrees.
- *Your arm is once again STRAIGHT!*

Rolling Ball Puzzle

1. Put a ball on a flat table.
2. Place hand flat on top of the ball
3. Make circular rubbing motion, as though polishing the tabletop.
4. Watch a point on the equator of the ball.
5. *small clockwise circles* $\longrightarrow$
   equator goes counterclockwise
6. *small counterclockwise circles* $\longrightarrow$
   equator goes clockwise

Rolling Ball Scenario

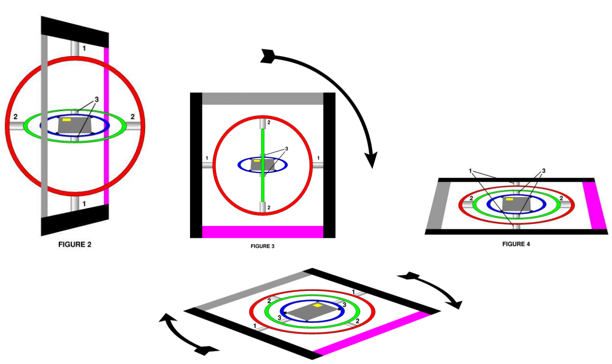


Gimbal Lock

Gimbal Lock occurs when a mechanical or computer system experiences an anomaly due to an (x, y, z)-based orientation control sequence.

- *Mechanical systems cannot avoid all possible gimbal lock situations .*

- *Computer orientation interpolation systems can avoid gimbal-lock-related glitches* **by using quaternion interpolation.**



Mechanical Gimbal Lock: Using x, y, z axes to encode orientation gives singular situations.

Gimbal Lock — Apollo Systems

Red-painted area = Danger of real Gimbal Lock

2D Rotations

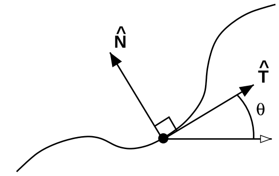
- 2D rotations $\leftrightarrow$ *complex numbers.*
- Why? $e^{i\theta}(x+iy) = (x'+iy')$

$$\begin{aligned} x' &= x\cos\theta - y\sin\theta \\ y' &= x\sin\theta + y\cos\theta \end{aligned}$$

- **Complex numbers** are a subspace of quaternions — so exploit 2D rotations to **introduce us to quaternions** and their geometric meaning.

Frames in 2D

The tangent and normal to 2D curve move continuously along the curve:



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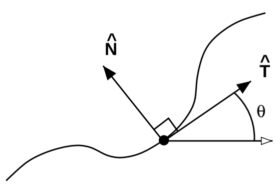

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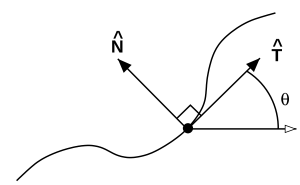


Frame Matrix in 2D

This motion is described at each point (or time) by the matrix:

$$\begin{aligned} R_2(\theta) &= \begin{bmatrix} \hat{\mathbf{T}} & \hat{\mathbf{N}} \end{bmatrix} \\ &= \begin{bmatrix} \cos\theta & -\sin\theta \\ \sin\theta & \cos\theta \end{bmatrix}. \end{aligned}$$

The Belt Trick Says:

There is a Problem...at least in 3D

How do you get $\cos\theta$ to know about 720 degrees?

The Belt Trick Says:

There is a Problem...at least in 3D

How do you get $\cos\theta$ to know about 720 degrees?

Hmmmmm. $\cos(\theta/2)$ knows about 720 degrees, right?

Half-Angle Transform:

A Fix for the Problem?

Let $a = \cos(\theta/2)$, $b = \sin(\theta/2)$,
(i.e., $\cos\theta = a^2 - b^2$, $\sin\theta = 2ab$),
and parameterize 2D rotations as:

$$R_2(a,b) \;=\; \begin{bmatrix} a^2-b^2 & -2ab \\ 2ab & a^2-b^2 \end{bmatrix}.$$

where orthonormality implies

$$(a^2+b^2)^2 = 1$$

which reduces back to $a^2 + b^2 = 1$.

Frame Evolution in 2D

Examine the time-evolution of a 2D frame (on our way to 3D).
First use $\theta(t)$ coordinates:

$$\begin{bmatrix} \hat{\mathbf{T}} & \hat{\mathbf{N}} \end{bmatrix} \;=\; \begin{bmatrix} \cos\theta & -\sin\theta \\ \sin\theta & \cos\theta \end{bmatrix}.$$

Differentiate to find frame equations:

$$\begin{aligned} \dot{\hat{\mathbf{T}}}(t) &= +\kappa\hat{\mathbf{N}} \\ \dot{\hat{\mathbf{N}}}(t) &= -\kappa\hat{\mathbf{T}}\,, \end{aligned}$$

where $\kappa(t) = d\theta/dt$ is the **curvature**.

Frame Evolution in (a,b):

The basis $(\hat{\mathbf{T}},\hat{\mathbf{N}})$ is nasty — **Four equations** with **Three constraints** from orthonormality, but just **One** true degree of freedom.

Major Simplification occurs in (a,b) coordinates!!

$$\dot{\hat{\mathbf{T}}} = 2\begin{bmatrix} a\dot{a} - b\dot{b} \\ a\dot{b} + b\dot{a} \end{bmatrix} = 2\begin{bmatrix} a & -b \\ b & a \end{bmatrix}\begin{bmatrix} \dot{a} \\ \dot{b} \end{bmatrix}$$

Frame Evolution in (a,b):

But this formula for $\dot{\hat{\mathbf{T}}}$ is just $\kappa\hat{\mathbf{N}}$, where

$$\kappa\hat{\mathbf{N}} = \kappa\begin{bmatrix} -2ab \\ a^2-b^2 \end{bmatrix} = \kappa\begin{bmatrix} a & -b \\ b & a \end{bmatrix}\begin{bmatrix} -b \\ a \end{bmatrix}$$

or

$$\kappa\hat{\mathbf{N}} = \kappa\begin{bmatrix} a & -b \\ b & a \end{bmatrix}\begin{bmatrix} 0 & -1 \\ 1 & 0 \end{bmatrix}\begin{bmatrix} a \\ b \end{bmatrix}$$

2D Quaternion Frames!

Rearranging terms, *both* $\dot{\hat{\mathbf{T}}}$ and $\dot{\hat{\mathbf{N}}}$ eqns reduce to

$$\begin{bmatrix} \dot{a} \\ \dot{b} \end{bmatrix} = \frac{1}{2}\begin{bmatrix} 0 & -\kappa \\ +\kappa & 0 \end{bmatrix}\cdot\begin{bmatrix} a \\ b \end{bmatrix}$$

This is the square root of frame equations.

2D Quaternions . . .

So *one equation* in the two *“quaternion”* variables (a, b) with the constraint $a^2+b^2 = 1$ contains *both* the frame equations

$$\dot{\hat{\mathbf{T}}} = +\kappa\hat{\mathbf{N}}$$

$$\dot{\hat{\mathbf{N}}} = -\kappa\hat{\mathbf{T}}$$

$\Rightarrow$ this is much better for computer implementation, etc.

Rotation as Complex Multiplication

If we let $(a + ib) = \exp(i\,\theta/2)$ we see that rotation is complex multiplication!

“Quaternion Frames” in 2D are just complex numbers, with

$\boxed{\text{Evolution Eqns = derivative of } \exp(i\,\theta/2)\text{!}}$

Rotation with no matrices!

Due to an extremely deep reason in Clifford Algebras,

$$a + ib = e^{i\theta/2}$$

represents rotations “more nicely” than the matrices $R(\theta)$.

$$(a' + ib')(a + ib) = e^{i(\theta'+\theta)/2} = A + iB$$

where if we *want* the matrix, we write:

$$R(\theta')R(\theta) = R(\theta' + \theta) = \begin{bmatrix} A^2 - B^2 & -2AB \\ 2AB & A^2 - B^2 \end{bmatrix}$$

The Algebra of 2D Rotations

The algebra corresponding to 2D rotations is easy: just complex multiplication!!

$$\begin{aligned} (a', b') * (a, b) &\cong (a' + ib')(a + ib) \\ &= a'a - b'b + i(a'b + ab') \\ &\cong (a'a - b'b,\ a'b + ab') \\ &= (A,\ B) \end{aligned}$$

2D Rotations are just **complex multiplication**, and take you around the unit circle!

Quaternion Frames

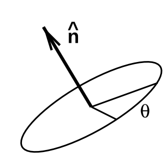
In 3D, repeat our trick: take square root of the frame, but now use *quaternions*:

- **Write down the 3D frame.**
- **Write as double-valued quadratic form.**
- **Rewrite frame evolution equations linearly in the new variables.**

The Geometry of 3D Rotations

We begin with a basic fact:

Euler theorem: *every* 3D frame can be written as a spinning by θ about a fixed axis $\hat{\mathbf{n}}$, the eigenvector of the rotation matrix:



Quaternion Frames . . .

The Matrix $R_3(\theta, \hat{\mathbf{n}})$ giving 3D rotation by θ about axis $\hat{\mathbf{n}}$ is :

$$\begin{bmatrix} c+(n_1)^2(1-c) & n_1n_2(1-c)-sn_3 & n_3n_1(1-c)+sn_2 \\ n_1n_2(1-c)+sn_3 & c+(n_2)^2(1-c) & n_3n_2(1-c)-sn_1 \\ n_1n_3(1-c)-sn_2 & n_2n_3(1-c)+sn_1 & c+(n_3)^2(1-c) \end{bmatrix}$$

where $c = \cos\theta$, $s = \sin\theta$, and $\hat{\mathbf{n}} \cdot \hat{\mathbf{n}} = 1$.

Can we find a 720-degree form?

Remember 2D: $a^2 + b^2 = 1$
then substitute $1 - c = (a^2+b^2) - (a^2-b^2) = 2b^2$
to find the remarkable expression for $\mathbf{R}(\theta, \hat{\mathbf{n}})$:

$$\begin{bmatrix} a^2-b^2+(n_1)^2(2b^2) & 2b^2n_1n_2-2abn_3 & 2b^2n_3n_1+2abn_2 \\ 2b^2n_1n_2+2abn_3 & a^2-b^2+(n_2)^2(2b^2) & 2b^2n_2n_3-2abn_1 \\ 2b^2n_3n_1-2abn_2 & 2b^2n_2n_3+2abn_1 & a^2-b^2+(n_3)^2(2b^2) \end{bmatrix}$$

Rotations and Quadratic Polynomials

Remember $(n_1)^2 + (n_2)^2 + (n_3)^2 = 1$ and $a^2 + b^2 = 1$;
letting

$$q_0 = a = \cos(\theta/2) \qquad \mathbf{q} = b\hat{\mathbf{n}} = \hat{\mathbf{n}}\sin(\theta/2)$$

We find a matrix $R_3(q)$

$$\begin{bmatrix} q_0^2+q_1^2-q_2^2-q_3^2 & 2q_1q_2-2q_0q_3 & 2q_1q_3+2q_0q_2 \\ 2q_1q_2+2q_0q_3 & q_0^2-q_1^2+q_2^2-q_3^2 & 2q_2q_3-2q_0q_1 \\ 2q_1q_3-2q_0q_2 & 2q_2q_3+2q_0q_1 & q_0^2-q_1^2-q_2^2+q_3^2 \end{bmatrix}$$

Quaternions and Rotations . . .

HOW does $q = (q_0, \mathbf{q})$ represent rotations?

LOOK at

$$R_3(\theta, \hat{\mathbf{n}}) \stackrel{?}{=} R_3(q_0, q_1, q_2, q_3)$$

THEN we can verify that choosing

$$q(\theta, \hat{\mathbf{n}}) = (\cos\frac{\theta}{2},\ \hat{\mathbf{n}}\sin\frac{\theta}{2})$$

makes the R_3 equation an *IDENTITY*.

Quaternions and Rotations . . .

WHAT happens if you do **TWO** rotations?

EXAMINE the action of two rotations

$$R(q')R(q) = R(Q)$$

EXPRESS in quadratic forms in q and LOOK FOR an analog of complex multiplication:

Quaternions and Rotations . . .

RESULT: the following multiplication rule
$\boxed{q' * q = Q}$ yields **exactly** the correct 3×3 rotation matrix $R(Q)$:

$$\begin{bmatrix} Q_0 = [q' * q]_0 \\ Q_1 = [q' * q]_1 \\ Q_2 = [q' * q]_2 \\ Q_3 = [q' * q]_3 \end{bmatrix} = \begin{bmatrix} q'_0q_0 - q'_1q_1 - q'_2q_2 - q'_3q_3 \\ q'_0q_1 + q'_1q_0 + q'_2q_3 - q'_3q_2 \\ q'_0q_2 + q'_2q_0 + q'_3q_1 - q'_1q_3 \\ q'_0q_3 + q'_3q_0 + q'_1q_2 - q'_2q_1 \end{bmatrix}$$

This is Quaternion Multiplication.

Algebra of Quaternions
= 3D Rotations!

2D rotation matrices are represented by **complex multiplication**

3D rotation matrices are represented by **quaternion multiplication**

Algebraic 2D/3D Rotations

Therefore in 3D, the 2D complex multiplication

$$(a', b') * (a, b) = (a'a - b'b,\ a'b + ab')$$

is replaced by 4D quaternion multiplication:

$$\begin{aligned} q' * q = (& q'_0 q_0 - q'_1 q_1 - q'_2 q_2 - q'_3 q_3, \\ & q'_0 q_1 + q'_1 q_0 + q'_2 q_3 - q'_3 q_2, \\ & q'_0 q_2 + q'_2 q_0 + q'_3 q_1 - q'_1 q_3, \\ & q'_0 q_3 + q'_3 q_0 + q'_1 q_2 - q'_2 q_1) \end{aligned}$$

Algebra of Quaternions . . .

The equation is easier to remember by dividing it into a *scalar* piece q_0 and a *vector* piece $\vec{q}$:

$$\begin{aligned} q' * q = (& q'_0 q_0 - \vec{q}' \cdot \vec{q}, \\ & q'_0 \vec{q} + q_0 \vec{q}' + \vec{q}' \times \vec{q}) \end{aligned}$$

Now we can SEE quaternions!

Since $(q_0)^2 + \mathbf{q} \cdot \mathbf{q} = 1$ then

$$q_0 = \sqrt{1 - \mathbf{q} \cdot \mathbf{q}}$$

Plot just the 3D vector: $\mathbf{q} = (q_x, q_y, q_z)$

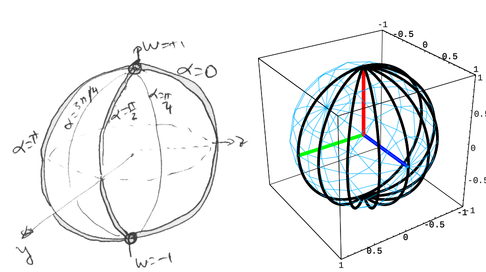
q_0 is KNOWN! We can also use any other triple: the fourth component is *dependent*.

DEMO

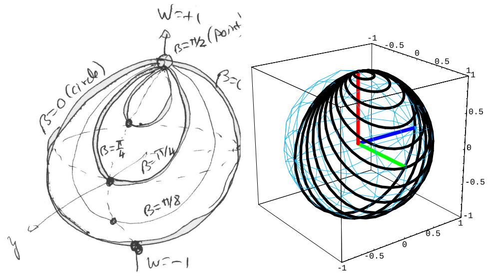
We can now make a Quaternion Picture of each of our favorite tricks

- 360° **Belt Trick in Quaternion Form.** DEMO:
- 720° **Belt Trick in Quaternion Form.**
- **Rolling Ball in Quaternion Form.** DEMO:
- **Gimbal Lock in Quaternion Form.**

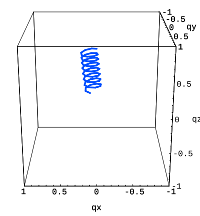
360° **Belt Trick in Quaternion Form**



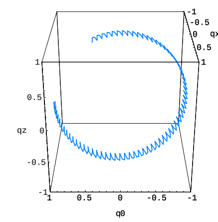
720° **Belt Trick in Quaternion Form**



Rolling Ball in Quaternion Form

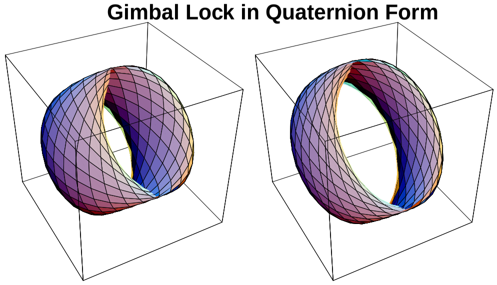


$\mathbf{q}$ vector-only plot.



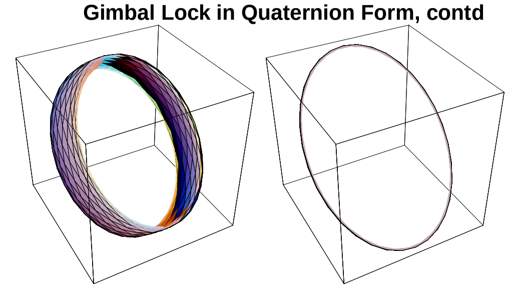
(q_0, q_x, q_z) plot

Gimbal Lock in Quaternion Form



Quaternion Plot of the *remaining* orientation degrees of freedom of $\mathbf{R}(\theta, \hat{\mathbf{x}}) \cdot \mathbf{R}(\phi, \hat{\mathbf{y}}) \cdot \mathbf{R}(\psi, \hat{\mathbf{z}})$ at $\phi = 0$ and $\phi = \pi/6$

Gimbal Lock in Quaternion Form, contd



Choosing ϕ and plotting the *remaining* orientation degrees in the rotation sequence $\mathbf{R}(\theta, \hat{\mathbf{x}}) \cdot \mathbf{R}(\phi, \hat{\mathbf{y}}) \cdot \mathbf{R}(\psi, \hat{\mathbf{z}})$, we see degrees of freedom **decrease from TWO to ONE as $\phi \to \pi/2$**

Quaternion Interpolations

- Shoemake (Siggraph '85) proposed using quaternions instead of Euler angles to get smooth frame interpolations without **Gimbal Lock**:

  BEST CHOICE: Animate objects and cameras using rotations represented on S^3 by quaternions

Interpolating on Spheres

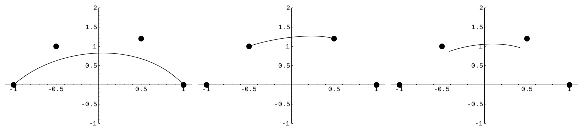
General quaternion spherical interpolation employs the "SLERP," a constant angular velocity transition between two directions, $\hat{\mathrm{q}}_1$ and $\hat{\mathrm{q}}_2$:

$$\begin{aligned} \hat{\mathrm{q}}_{12}(t) &= \mathrm{Slerp}(\hat{\mathrm{q}}_1, \hat{\mathrm{q}}_2, t) \\ &= \hat{\mathrm{q}}_1 \frac{\sin((1-t)\theta)}{\sin(\theta)} + \hat{\mathrm{q}}_2 \frac{\sin(t\theta)}{\sin(\theta)} \end{aligned}$$

where $\cos\theta = \hat{\mathrm{q}}_1 \cdot \hat{\mathrm{q}}_2$.

Plane Interpolations

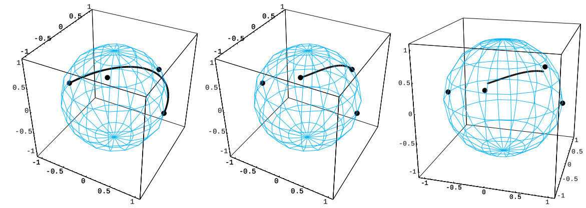
In Euclidean space, these three basic cubic splines look like this:



Bezier — Catmull-Rom — Uniform B

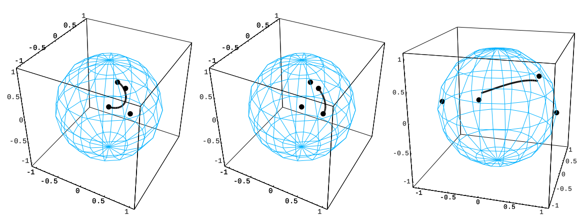
The differences are in the derivatives: Bezier has to start matching all over at every fourth point; Catmull-Rom matches the first derivative; and B-spline is the cadillac, matching all derivatives but *no control points*.

Spherical Interpolations



Bezier — Catmull-Rom — Uniform B

Quaternion Interpolations



Bezier — Catmull-Rom — Uniform B

Exp Form of Quaternion Rotations

In Hamilton's notation, we can generalize the 2D equation

$$a + ib = e^{i\theta/2}$$

Just set

$$\begin{aligned} q &= (q_0, q_1, q_2, q_3) \\ &= q_0 + \mathbf{i}q_1 + \mathbf{j}q_2 + \mathbf{k}q_3 \\ &= e^{(\mathbf{I}\cdot\hat{\mathbf{n}}\theta/2)} \end{aligned}$$

with $q_0 = \cos(\theta/2)$ and $\vec{\mathbf{q}} = \hat{\mathbf{n}}\sin(\theta/2)$ and $\mathbf{I} = (\mathbf{i}, \mathbf{j}, \mathbf{k})$, with $\mathbf{i}^2 = \mathbf{j}^2 = \mathbf{k}^2 = -1$, and $\mathbf{i} * \mathbf{j} = \mathbf{k}$ (cyclic),

Cute Quaternion Tricks!

Square Roots are cool..

A quaternion p is the **square root** of a quaternion q if

$$p * p = q\ .$$

A hint: remember that if $c = \cos\theta$, and $\gamma = \cos(\frac{\theta}{2})$, then

$$\gamma = \sqrt{\frac{1+c}{2}} = \frac{1+c}{\sqrt{2(1+c)}}$$

Cute Quaternion Tricks...

Suppose we now look at $1 + q = (1 + q_0, \mathbf{q})$. Then

$$\begin{aligned} (1+q)*(1+q) &= \left((1+q_0)^2 - \mathbf{q}\cdot\mathbf{q},\ 2\mathbf{q}(1+q_0)\right) \\ &= 2(1+q_0)\,q \end{aligned}$$

Dividing through by $2(1+q_0)$, we find the $\boxed{\textbf{square root:}}$

$$p = \sqrt{q} = \frac{1+q}{\sqrt{2(1+q_0)}}$$

Tricks, contd: Lining up $\hat{a}$ and $\hat{b}$

A common rotation task is to line up two directions, $\hat{a}$ and $\hat{b}$. There is a simple **quaternion form** for this operation. Let

$$\hat{a}\cdot\hat{b} = \cos\theta = c\,, \quad \hat{a}\times\hat{b} = \hat{n}\sin\theta$$

where we assume $\sin\theta > 0$. Then we can compute the rotation from $\hat{a}$ to $\hat{b}$ using, again, the half-angle formula:

$$\begin{aligned} R(\hat{a},\hat{b}) &= (\cos(\theta/2),\, \hat{n}\sin(\theta/2)) \\ &= \left(\sqrt{\frac{1+c}{2}},\, \hat{a}\times\hat{b}\sqrt{\frac{1}{2(1+c)}}\right) \end{aligned}$$

where we also used $\sin\theta = 2\cos(\theta/2)\sin(\theta/2)$.

Clifford Algebras

- **All Rotations in any dimension are represented by *two reflections* using Clifford Algebra:**
  $\mathbf{A}$ and $\mathbf{B}$ define the perpendicular directions to two reflection planes, $\mathbf{A}\cdot\mathbf{A} = \mathbf{B}\cdot\mathbf{B} = 1$.
- **Create Rotation Matrix $\mathbb{R}$ and solve for the Quaternion, and you amazingly get THIS:**

$$q(\mathbf{A},\mathbf{B}) = (\mathbf{A}\cdot\mathbf{B},\, \mathbf{A}\times\mathbf{B})$$

Clifford Algebra Quaternion Form . . .

Why is this a quaternion form?

$$\begin{aligned} q\cdot q &= (\mathbf{A}\cdot\mathbf{B})^2 + (\mathbf{A}\times\mathbf{B})\cdot(\mathbf{A}\times\mathbf{B}) \\ &= (\mathbf{A}\cdot\mathbf{A})\,(\mathbf{B}\cdot\mathbf{B}) \\ &\equiv 1 \end{aligned}$$

If Quaternions are like the Square Roots of Rotations, then Clifford Algebras are like the Square Roots of Quaternions!

Key to Quaternion Intuition

Fundamental Intuition: We know

$$q_0 = \cos(\theta/2), \quad \vec{q} = \hat{n}\sin(\theta/2)$$

We also know that *any coordinate frame* M can be written as $M = R(\theta,\hat{n})$.

Therefore

$\vec{q}$ points exactly along the axis we have to rotate around to go from identity I to M, and the length of $\vec{q}$ tells us how much to rotate.

Summarize Quaternion Properties

- **Unit four-vector.** Take $q = (q_0, q_1, q_2, q_3) = (q_0, \vec{q})$ to obey constraint $q\cdot q = 1$.
- **Multiplication rule.** The quaternion product q and p is
  $q * p = (q_0 p_0 - \vec{q}\cdot\vec{p},\, q_0\vec{p} + p_0\vec{q} + \vec{q}\times\vec{p})$,
  or, alternatively,

$$\begin{bmatrix} [q*p]_0 \\ [q*p]_1 \\ [q*p]_2 \\ [q*p]_3 \end{bmatrix} = \begin{bmatrix} q_0p_0 - q_1p_1 - q_2p_2 - q_3p_3 \\ q_0p_1 + q_1p_0 + q_2p_3 - q_3p_2 \\ q_0p_2 + q_2p_0 + q_3p_1 - q_1p_3 \\ q_0p_3 + q_3p_0 + q_1p_2 - q_2p_1 \end{bmatrix}$$

Quaternion Summary . . .

- **Rotation Correspondence.** The unit quaternions q and $-q$ correspond to a single 3D rotation R_3:

$$\begin{bmatrix} q_0^2+q_1^2-q_2^2-q_3^2 & 2q_1q_2-2q_0q_3 & 2q_1q_3+2q_0q_2 \\ 2q_1q_2+2q_0q_3 & q_0^2-q_1^2+q_2^2-q_3^2 & 2q_2q_3-2q_0q_1 \\ 2q_1q_3-2q_0q_2 & 2q_2q_3+2q_0q_1 & q_0^2-q_1^2-q_2^2+q_3^2 \end{bmatrix}$$

If

$$q = (\cos\frac{\theta}{2}, \hat{n}\sin\frac{\theta}{2})\,,$$

with $\hat{n}$ a unit 3-vector, $\hat{n}\cdot\hat{n} = 1$. Then $R(\theta,\hat{n})$ is usual 3D rotation by θ in the plane $\perp$ to $\hat{n}$.

SUMMARY

- **Quaternions represent 3D frames**
- **Quaternion multiplication represents 3D rotation**
- **Quaternions are points on a hypersphere**
- **Quaternions paths can be visualized with 3D display**
- **Belt Trick, Rolling Ball, and Gimbal Lock can be understood as Quaternion Paths.**