On Reconfiguring Tree Linkages:
Trees can Lock

Therese Biedl∗ Erik Demaine∗ Martin Demaine∗
Sylvain Lazard† Anna Lubiw∗ Joseph O’Rourke† Steve Robbins§
Ileana Streinu‡ Godfried Toussaint§ Sue Whitesides§

February 1, 2008

Abstract
It has recently been shown that any simple (i.e. nonintersecting) polygo-
nal chain in the plane can be reconfigured to lie on a straight line, and
any simple polygon can be reconfigured to be convex. This result cannot
be extended to tree linkages: we show that there are trees with two
simple configurations that are not connected by a motion that preserves
simplicity throughout the motion. Indeed, we prove that an \( N \)-link tree
can have \( 2^{\Omega(N)} \) equivalence classes of configurations.

1 Introduction
Consider a graph, each edge labelled with a positive number. Such a graph may
be thought of as a collection of distance constraints between pairs of points in
a Euclidean space. A realization of such a graph maps each vertex to a point,
also called a joint, and maps each edge to the closed line segment, called a
link, connecting its incident joints. The link length must equal the label of the
underlying graph edge. If a graph has one or more such realizations, we call it
a linkage.

An embedding of a linkage in space is called a configuration of the linkage
if any pair of links whose underlying edges are incident on a common vertex
intersect only at the common joint and all other pairs of links are disjoint. Some
authors allow the term configuration to refer to objects that self-intersect. In

Research partially supported by \textit{Fonds pour la Formation de Chercheurs et l’Aide à la
Recherche}, Québec (SW,SR), the \textit{Natural Sciences and Engineering Research Council}, Canada
(AL,GT,SW,ED) and the \textit{National Science Foundation}, USA (JO,IS).

∗University of Waterloo, Waterloo, Canada. \{biedl, eddemaine, mldemaine, alubiw\}@uwaterloo.ca.
†INRIA Lorraine, France. lazard@loria.fr.
‡Smith College, Northampton, USA. \{orourke, streinu\}@cs.smith.edu.
§McGill University, Montreal, Canada. \{stever, godfried, sue\}@cgm.cs.mcgill.ca.
contrast, we require all configurations to be simple; i.e. non self-intersecting. A motion of a linkage is a continuous movement of its joints such that it remains in a valid configuration at all times. A natural question is whether a motion exists between two given configurations of a linkage.

For a linkage in the plane whose underlying graph is a path, a related question is whether it can always be straightened; i.e. whether it can be moved from any configuration to lie on a straight line. Similarly, we wonder whether a cycle linkage (polygon) can always be convexified; i.e. whether it can be moved to a configuration that is a convex polygon. If a linkage cannot be so reconfigured, it is called locked. These questions have been in the math community since the 1970's [22] and in the computational geometry community since 1991 [18, 19], but first appeared in print in 1993 and 1995: [20] and [10, p. 270]. Initial computational geometry results focused on certain classes of configurations such as “visible” chains [4], star-shaped polygons [9] and monotone polygons [3]. Connelly, Demaine, and Rote have recently proved that in the plane, no chain or polygon is locked [7]; Streinu [28] provides an alternative proof. In three dimensions, while a complete characterization isn’t known, there are configurations of open polygonal chains and of polygons that can be straightened, or convexified, respectively, and other configurations that can not be [1]. In four or more dimensions, no chain or polygon is

Related linkage motion results in the computational geometry literature (e.g. [10–14, 17, 21, 23–26, 29–31]) allow the links to cross or to pass through or over one another. In other words, the links represent distance constraints between joints, not physical obstacles that must avoid each other. There is also the very general algebraic approach to motion planning of [5] and [27], since the constraint that the links not cross can be specified algebraically. For related work from a topological point of view, see [15] and references therein; again, this work allows links to cross.

There is a natural equivalence relation on the set of linkage configurations: two configurations are equivalent if there is a motion that takes the linkage from one configuration to the other. The Connelly-Demaine-Rote result states that chains in the plane have a single equivalence class of configurations. In this report we show that their result cannot be generalized to tree linkages: trees can have many configuration classes.

This report establishes that a suitably-constructed tree linkage has two configurations (pictured in Figure 1) for which no motion between them is possible. (This result also answers a question posed in [3], arising from a paper folding problem.) As a corollary, we obtain the result that an $N$-link tree linkage can exhibit $2^{2(N)}$ equivalence classes of configurations.

The rest of this report is organized as follows. Section 2 gives definitions and the basic idea for constructing a locked tree configuration, Section 3 gives the construction itself, and Sections 4 and 5 give the correctness proof. Section 6 concludes with some open problems.
2 Preliminaries

In this section, we introduce the technical definitions used. From now on, we often do not distinguish between vertices and edges in the underlying tree, the corresponding joints and links in the tree linkage, and the points and line segments occupied by the joints in links in a particular configuration. The context should make the meaning clear.

The trees considered in this report consist of \( n \) petals, each comprised of three links. The initial configuration is sketched in Figure 2 and detailed as the report unfolds.

The petals all meet at joint \( O \); the other joints of petal \( i \) are labelled \( A_i, B_i, \)
and \( C \). Designate the petal angle as \( \theta_i = \angle A_{i-1}OA_i \); let \( \bar{\theta} = 2\pi/n \). All index arithmetic is taken mod \( n \); all angles are measured in the interval \([0, 2\pi)\). The link lengths are as follows: \( \|OA_i\| = 1 \), \( \|A_iB_i\| = l_1 \), and \( \|B_iC_i\| = l_2 \), where for two points in the plane, \( X \) and \( Y \), we use \( XY \) to designate the closed line segment between \( X \) and \( Y \), and \( \|XY\| \) to denote its length. The values of \( l_1 \) and \( l_2 \) will be discussed in Section 3.

We often focus on a single petal at a time, so the notation is simplified by suppressing the petal index. Joints of petal \( i \) are referred to as \( A, B, \) and \( C \), joint \( A_{i-1} \) is denoted \( A' \), and the petal angle, i.e., \( \angle A'O \), as just \( \theta \). Let \( L \) be the line through \( OA' \), and choose a reference frame with \( L \) oriented horizontally, \( O \) to the left of \( A' \).

### 2.1 The Intuition

We first give a brief outline of the main argument, before delving into the details.

![Figure 3: Illustrating the definition of restricted configuration.](image-url)

In the initial configuration, all petals are in a congruent configuration, pictured in Figure 3, with petal angle \( \bar{\theta} = 2\pi/n \). By choosing \( l_1 \) long enough, we ensure that link \( AB \) cannot swing out so as to straighten joint \( A \). Thus, the petal angle must be increased before joint \( A \) can straighten. Because the petals all join at \( O \), opening up one petal necessitates squeezing the other petals.

Consider now how small we can squeeze a petal angle. By choosing \( l_2 \) long enough, we ensure that link \( BC \) cannot swing over to fold up against link \( AB \). In fact, joint \( C \) is trapped inside quadrilateral \( \Box ORBS \). We show later that the smallest petal angle is obtained by moving joint \( C \) to \( O \), pictured in Figure 3. Lengthening \( l_2 \) increases this minimum petal angle, so by choosing \( l_2 \) long enough, we can ensure that squeezing \( n-1 \) petals to their minimum angle
is still not enough to let the last petal open. This, in essence, is why the tree is locked.

From the above discussion, we note that \( l_1 \) and \( l_2 \) must be chosen “long enough”. On the other hand, they must also be “short enough” that the configuration shown in Figure 3 is achievable. Section 3 details all the constraints needed to satisfy these two requirements. Section 4 defines a “restricted” class of petal configurations (to which the configuration in Figure 3 belongs) and proves that there is a non-zero minimum petal angle for this class of configurations. Finally, Section 5 proves that a linkage with parameters \( n, l_1, \) and \( l_2 \), satisfying all the constraints of Section 3, can be put into a initial configuration that is locked.

3 Constructing a Locked Tree

This section details the constraints on the parameters \( n, l_1, \) and \( l_2 \) that are necessary to construct our locked linkage. Lemma 1 at the end of this section, demonstrates that the constraints are simultaneously satisfiable. Refer to Figure 3 throughout this section.

A three-link petal cannot be locked if the petal angle is greater than or equal to \( \pi/2 \). Thus we must have the initial petal angle \( \bar{\theta} = 2\pi/n \) strictly less than \( \pi/2 \), or

\[
 n > 4. \tag{1}
\]

Henceforth, assume \( \theta < \pi/2 \). We want to have joint \( B \) to the left of the vertical line through \( A \). In order that link \( AB \) fits, we must have

\[
 l_1 < 1. \tag{2}
\]

For any configuration of a petal, let \( C \) be the circle centred at \( A \) with radius \( l_1 \). Let \( \beta \) be the petal angle at which \( C \) is tangent to \( L \),

\[
 \beta = \arcsin l_1. \tag{3}
\]

The range for the principal value of arcsine is \([ -\pi/2, \pi/2 ]\). However, we know that \( l_1 \) must be positive, and less than 1 (Inequality 2), so \( \beta \) is actually in the range \((0, \pi/2)\).

When \( \theta < \beta \), circle \( C \) will properly intersect \( L \). We want this to be true for the initial configuration, in which all petal angles are \( \bar{\theta} \), so we require

\[
 \bar{\theta} < \beta. \tag{4}
\]

Suppose \( C \) properly intersects \( L \) and let \( P \) be the leftmost intersection point. Applying the cosine rule to \( \triangle OAP \) and noting that \( \|OA\| = 1 \) and \( \|AP\| = l_1 \), yields

\[
 l_1^2 = \|OP\|^2 + 1 - 2\|OP\| \cos \theta. \tag{5}
\]

Since \( l_1 \), the radius of \( C \), is strictly less than \( \|OA\| = 1 \) by Inequality 3, joint \( O \) is outside the circle \( C \). From this, and \( \theta < \pi/2 \), it follows that \( P \) is to the right of \( O \), and hence \( \|OP\| \) is the smaller root of the quadratic equation. We define the function

\[
 l_P(\theta) = \|OP\| = \cos \theta - \sqrt{l_1^2 - \sin^2 \theta}. \tag{5}
\]
This function is only defined on values of $\theta$ for which $C$ intersects $L$; i.e., for $\theta$ in $[0, \beta]$. Differentiating shows that $l_\theta$ is a strictly increasing function on this interval.

Furthermore, $P$ is to the left of the vertical line through $A$, and hence $P \in OA'$, but $P$ is not at $A'$. We know that $A$ is inside the circle $C$, while $O$ is outside, so $C$ intersects $OA$; let $Q$ be this intersection point. Note that the small arc $PQ$ of $C$ lies inside $\triangle A'OA$.

Suppose $\theta < \beta$, and $B$ is on the small arc $PQ$ of $C$. Then $B$ is inside $\triangle A'OA$. Since the triangle is isosceles, and the angle $\theta$ is $< \pi/2$, $\triangle A'OA$ is acute. This ensures that there is a line passing through $B$ perpendicular to each edge of the triangle. Let $R \in OA'$ be such that $BR \perp OA'$ and $S \in OA$ be such that $BS \perp OA$. We want to have joint $C$ inside quadrilateral $\square ORBS$. This is feasible for the initial configuration if we choose

$$l_2 < l_\theta(\bar{\theta}),$$

for then we may place $B$ near $P$, and $C$ along $OB$. At the same time, we wish to have $l_2$ long enough that $C$ remains trapped in $\square ORBS$. This is ensured by choosing

$$l_2 > \sin \beta \cos \beta,$$

as we show later in Section 4.

Define

$$\alpha = (2\pi - \beta)/(n - 1).$$

Later, we will see that if a petal angle is opened past $\beta$, then some other petal angle must be smaller than $\alpha$. The proof that the tree is locked then hinges on showing that there is a minimal petal angle, which is greater than $\alpha$.

To obtain a non-zero minimal petal angle, we require

$$l_1 + l_2 > 1,$$  

for otherwise, links $AB$ and $BC$ could fold flat against link $OA$, and the petal angle could squeeze to zero. Indeed, we show later, in Lemma 3, that the minimum possible petal angle is bounded from below by the petal angle obtained in the non-simple configuration with $C$ at $O$, and $B \in OA'$, pictured in Figure 4. Define $\theta_m$ to be the resulting petal angle. With $\triangle OAB$, the cosine rule yields

$$l_1^2 = l_2^2 + 1 - 2l_2 \cos \theta_m,$$

or

$$\theta_m = \arccos \left( \frac{1 - l_1^2}{2l_2} \right).$$

We are using the principal value of arccosine, so $\theta_m \in [0, \pi]$.

Finally, in order to prove Theorem 5, we assume that $l_1$ and $l_2$ are such that

$$\alpha < \theta_m.$$  

We prove, in Appendix A, the following lemma which states that all the constraints of this section may be simultaneously satisfied by an appropriate
choice of \( n, l_1, \) and \( l_2. \) For \( n = 5, \) calculation shows that \( l_1 = 0.9511 \) and \( l_2 = 0.299 \) satisfy the system of inequalities above, with \( 71.997984 < 71.998224 < 72 < 72.008064 \) (angles in degrees) for \( \alpha, \theta_m, \tilde{\theta}, \) and \( \beta, \) respectively.

**Lemma 1** For each integer \( n > 4, \) there exists two real numbers \( l_1 \) and \( l_2 \) satisfying simultaneously all the constraints of Section 3 (i.e., Inequalities \( \text{[2], [4], [6], [7], [9], and [11]} \).

In the sequel, we assume some choice of parameters has been made such that all the constraints of this section hold.

## 4 Restricted Configurations

Referring to Figure 3, recall from the definition of \( \beta \) (Equation \( [8] \)) that \( \theta < \beta \) implies that circle \( C \) properly intersects link \( OA'. \) Thus, points \( P \) and \( Q \) are well-defined. When joint \( B \) is on the small arc \( PQ, \) recall that points \( R \) and \( S \) are also well-defined. And finally, joint \( C \) also fits inside \( \text{\( \Box ORBS, \) due to Inequality [8]}. \)

**Definition:** A petal configuration is said to be restricted if the following conditions hold:

(i) \( \theta < \beta, \)

(ii) \( B \) is on the open small arc \( PQ \) of \( C, \) and

(iii) \( C \) is in the open region bounded by the quadrilateral \( \text{\( \Box ORBS. \) \}

Note in Figure 3 that \( \| BR \| \) and \( \| BS \| \) are both smaller than \( \| BC \|. \) We show now that this is always the case in a restricted configuration.

**Lemma 2** In a restricted configuration, both \( \| BR \| \) and \( \| BS \| \) are strictly less than \( l_2. \)
Proof: For a point \( X \), let \( d(X, L) \) denote the distance from \( X \) to the line \( L \) through \( O \) and \( A' \). We have that \( \|BR\| = d(B, L) \). Because \( B \) is on the small arc \( PQ \), \( d(B, L) \leq d(Q, L) = \|OQ\| \sin \theta \). Hence,

\[
\|BR\| \leq \|OQ\| \sin \theta. \tag{12}
\]

By similar reasoning,

\[
\|BS\| \leq \|OP\| \sin \theta. \tag{13}
\]

Note that \( \|OQ\| = 1 - l_1 = 1 - \sin \beta \), by Equation 3. For \( x \in [0, \pi/2] \), \( \sin x + \cos x \geq 1 \), so \( \|OQ\| \leq \cos \beta \). Because \( l_P \) is an increasing function, \( \|OP\| = l_P(\theta) \leq l_P(\beta) \), and \( l_P(\beta) \leq \cos \beta \), by Equation 5.

Both \( \|OP\| \) and \( \|OQ\| \) are \( \leq \cos \beta \). Hence, by Inequalities 12 and 13, both \( \|BR\| \) and \( \|BS\| \) are bounded from above by \( \cos \beta \sin \theta < \cos \beta \sin \beta \), as \( \theta < \beta \leq \pi/2 \) by assumption. But this is strictly less than \( l_2 \) by Inequality 7.

Lemma 3 In a restricted configuration, \( \theta \geq \theta_m \).

Proof: Suppose, for contradiction, the petal is in a restricted configuration with \( \theta < \theta_m \).

Consider the two triangles \( \triangle OAB \) and \( \triangle OAP \). These triangles share the common side \( OA \), and \( \|AB\| = \|AP\| = l_1 \). Two sides of \( \triangle OAB \) are equal length with two sides of \( \triangle OAP \). Moreover the included angles satisfy \( \angle OAB < \angle OAP \), since by definition of restricted configuration (condition (ii)), joint \( B \) lies on the small arc \( PQ \) of \( C \). Applying the cosine law to the remaining side in each triangle (or using Euclid’s Proposition 24, Book I) we see \( \angle OAB < \angle OAP \) implies \( \|OB\| < \|OP\| \). By definition (Equation 2) \( \|OP\| = l_P(\theta) \), which is less than \( l_P(\theta_m) \) since \( l_P \) is an increasing function. A direct computation shows that \( l_P(\theta_m) = l_2 \), so we have \( \|OB\| < l_2 \).

By Lemma 3 we have also \( \|BR\| < l_2 \) and \( \|BS\| < l_2 \).

All four points \( O, R, B \) and \( S \) are strictly inside the circle of radius \( l_2 \) centred at \( B \). Joint \( C \) is of course on this circle, so it cannot be inside \( \odot ORBS \). This contradicts condition (iii) of a restricted configuration.

Lemma 4 Consider a petal in a restricted configuration. Throughout any motion during which \( \theta \) is strictly less than \( \beta \), the petal remains in a restricted configuration.

Proof: Note that the points \( P, Q, R, S \), and the circle \( C \), are defined by the positions of the joints \( A \) and \( B \); as the joints move, so do the points \( P, Q \), etc. For simplicity, we omit displaying this dependence on time.

Consider, in turn, the three conditions required for a restricted configuration. Condition (i) holds throughout the motion by assumption.

In any configuration, \( B \) must be on \( C \). Since \( B \) starts the motion on the small arc \( PQ \), for condition (ii) to be violated, \( B \) must pass through point \( P \) or through point \( Q \). \( P \) and \( Q \) are on the interior of links \( OA' \) and \( OA \), respectively,
and since $\theta < \beta$, $C$ always properly intersects these links. Thus $B$ may not move through $P$ or $Q$, and hence condition (ii) holds throughout the motion.

Given that $B$ remains on the small arc $PQ$, points $R$ and $S$ are well defined. Given that $B$ remains on the small arc $PQ$, points $R$ and $S$ are well defined. As $C$ starts the motion inside $\triangle ORBS$, condition (iii) is violated only if $C$ passes through one of the sides of this quadrilateral. Sides $OR$ and $OS$ are portions of links, so $C$ may not pass through them. By Lemma 2, $\|BR\|$ and $\|BS\|$ are both strictly less than $\|BC\|$, so $C$ cannot pass through side $BR$ or side $BS$. Thus, condition (iii) holds throughout the motion. $\square$

5 Trees Can Lock

This section describes our main result: two inequivalent configurations of a tree linkage.

Recall that $\theta_m$ is defined by a triangle with sides $1$, $l_1$, and $l_2$, pictured in Figure 4. With $\triangle OAB$, the cosine rule yields

$$l_1^2 = l_2^2 + 1 - 2l_2 \cos \theta_m,$$

while from Inequality $\frac{1}{\theta}$ we can obtain

$$l_1^2 < l_2^2 + 1 - 2l_2 \cos \bar{\theta},$$

which implies $\theta_m < \bar{\theta}$. Putting this together with Inequalities $\frac{1}{\theta}$ and $\frac{1}{\theta}$ we have

$$\alpha < \theta_m < \bar{\theta} < \beta,$$

hence $(\alpha, \beta)$ is a non-empty interval.

Consider a tree in a configuration in which the petal configurations are all congruent, with petal angles all equal to $\bar{\theta} \in (\alpha, \beta)$. We place joint $B$ on the small arc $PQ$. Because $l_2 < l_1(\bar{\theta}) = \|OP\|$ (Inequality $\frac{1}{\theta}$) we can place $B$ near, but not at, $P$ to ensure $\|OB\| > \|BC\|$. This ensures that joint $C$ may be placed along $OB$, which is inside $\square ORBS$. This is a valid configuration, and furthermore each petal configuration restricted. The next theorem shows all petals remain bounded from below by $\alpha$.

Theorem 5 Consider a tree of $n$ petals in a configuration such that $\theta_i \in (\alpha, \beta)$ for $0 \leq i < n$, and with each petal in a restricted configuration. During any motion, all petal angles remain in the range $(\alpha, \beta)$.

Proof: Suppose, to the contrary, a motion exists that takes some petal angle out of the range $(\alpha, \beta)$. Let $t_\alpha$ be the first instant that some petal angle, say for petal $k$, reaches $\alpha$. Let $t_\beta$ be the first instant that some petal angle reaches $\beta$. If $t_\beta < t_\alpha$, then at time $t_\beta$ all angles are strictly greater than $\alpha$ and at least one is equal to $\beta$. This means

$$2\pi = \sum_{i=0}^{n-1} \theta_i > (n-1)\alpha + \beta = 2\pi,$$
a contradiction. Hence $t_\alpha \leq t_\beta$.

During the supposed motion, the joint angles change continuously in time. Since $\alpha < \theta_m$ by Inequality 11, and $\theta_k$ approaches $\alpha$ from above as $t$ approaches $t_\alpha$ from below, we may choose $t_0 < t_\alpha$ such that $\theta_k \in (\alpha, \theta_m)$ at time $t_0$.

Note that during the motion up to time $t_0$, all petal angles are strictly less than $\beta$, as $t_0 < t_\alpha \leq t_\beta$. By Lemma 4 all petals remain in a restricted configuration before time $t_0$, so Lemma 3 applies to petal $k$. This means $\theta_k \geq \theta_m$, contradicting the choice of $t_0$.

Recall that two simple configurations of a tree linkage are equivalent if one can be moved to the other. Our main result is that a tree linkage can have two inequivalent configurations: one with all petals in a restricted configuration, and the other with one or more petal angles less than $\alpha$. These configurations are illustrated in Figure 1. This result can easily be extended to the following corollary.

**Corollary 6** There exist $N$-link tree linkages such that the linkages have $2^{\Omega(N)}$ equivalence classes of simple configurations.

![Figure 5: A tree linkage formed by joining $k$ copies of a lockable tree. Each subtree may be in either an open (as is the middle subtree) or a closed (the first and last subtrees) configuration. This linkage has at least $2^k$ configuration classes.](image)

**Proof:** Consider the linkage in Figure 5, in which there are $k$ copies of an eight-petal lockable tree connected by long links joining the $O$ joints of the subtrees. The connecting links are long enough that when they are stretched out to form a straight chain, each subtree can be in either an open or a closed configuration without crossing links.

Consider simple configurations in which the long links form a straight chain, and each subtree is in either an open or a closed configuration. Label such configurations by a $k$-bit vector, specifying for each subtree, whether its configuration is open or closed. Configurations with different labels are clearly not equivalent, as a motion of the entire linkage that would take some subtree in a closed configuration to an open configuration would imply, by removing links outside the subtree, the existence of a motion that would make petal angle of
the subtree inferior to $\alpha$. Hence the number of inequivalent configurations is at least $2^k \in 2^{\Omega(N)}$, as $N = 24k + (k - 1)$.

6 Conclusion

While no chain or polygon in the plane may lock, we showed in this report that for a tree linkage can; i.e. that there can be more than one equivalence class of simple configurations. Indeed, some $N$-link trees have $2^{\Omega(N)}$ equivalence classes.

The tree construction of Section 3 constrains the link lengths to be non-equal (it appears difficult to even get them nearly equal). This prompts the following question: can a tree linkage with equal-length links have a locked configuration? One “nearly equilateral” tree linkage is shown in Figure 6. We conjecture that if the link lengths are very nearly equal, this configuration is locked; the intuition is as follows. Each of the six triangular petals cannot collapse, so each remains nearly an equilateral triangle. If that is the case, it seems that each petal can only move by pivoting about its degree-3 joint, which it cannot do without crossing a link of the adjacent petal. Notice, however, that if the links truly

![Figure 6: A nearly equilateral tree linkage configuration.](image)

are of equal length, the configuration pictured cannot be simple.

The nearly equilateral example has the feature that the graph has maximum degree three. It is easy to replace a high-degree joint with a number of degree-three joints joined by a chain of tiny links. Do equilateral locked tree linkages with maximum degree three exist?

Finally, many interesting questions can be posed for linkages moving in higher dimensions. See [1, 6] for recent work on chain and cycle linkages moving under simple motion in three and more dimensions.
Acknowledgments

The research reported here was initiated at the International Workshop on Wrapping and Folding, co-organized by Anna Lubiw and Sue Whitesides, at the Bellairs Research Institute of McGill University, January 31 – February 6, 1998. We would like to thank Hazel Everett for many useful discussions.

Our locked tree was inspired by a polygonal chain designed by Joe Mitchell, kindly shared with one of the coauthors. In particular, we borrowed the circular structure from his example.

A preliminary version of this work appeared in [2].

A Proof of Lemma 1

This appendix proves the following lemma.

For each integer \( n > 4 \), there exists two real numbers \( l_1 \) and \( l_2 \) satisfying simultaneously all the constraints of Section 3 (i.e., Inequalities 2, 4, 6, 7, 9, and 11).

Proof:

We show that \( l_1 = \sin(\bar{\theta} + \epsilon) \) and \( l_2 = l_P(\bar{\theta} - \epsilon/n) \) are feasible link lengths, where \( \epsilon = 0.01^\circ \) is feasible for \( n = 5, n = 6 \) and any \( 0 < \epsilon < 0.4^\circ \) is feasible for \( n \geq 7 \). The proof consists of checking, in turn, each of the constraints mentioned above.

Constraint 1

Given our choice of \( l_1 \), this is satisfied as long as \( \bar{\theta} + \epsilon < \pi/2 \). Recall that \( \bar{\theta} = 2\pi/n \) and \( n \geq 5 \) (Inequality 1), so \( \bar{\theta} \leq \frac{2\pi}{5} \). Since \( \epsilon < 0.4^\circ \), the constraint is satisfied.

Constraint 2

By the definition of \( \bar{\theta} \) (Equation 3), and our choice of \( l_1 \), we have \( \beta = \bar{\theta} + \epsilon \). Since \( \epsilon > 0 \), the constraint is satisfied.

Constraint 4

Since \( \epsilon > 0 \), \( \bar{\theta} - \epsilon/n < \bar{\theta} \). Using the definition \( \bar{\theta} = 2\pi/n \), we see that \( \bar{\theta} - \epsilon/n < (2\pi - \epsilon)/n \). Since \( \epsilon < 0.4^\circ \), \( \bar{\theta} - \epsilon/n > 0 \). Now, \( l_P(\theta) \) is an increasing function on \( [0, \beta] \supset (0, \bar{\theta}) \), and \( l_2 = l_P(\bar{\theta} - \epsilon/n) \), so the constraint is satisfied.

We summarize, for future reference, some inequalities derived so far,

\[
0 < \bar{\theta} - \epsilon/n < \bar{\theta} < \beta = \bar{\theta} + \epsilon < \pi/2.
\]  \hfill (15)

Constraint 5

This constraint is the only one for which we distinguish cases based on \( n \). For \( n = 5 \) and \( n = 6 \), a direct calculation shows that the given link lengths (with \( \epsilon = 0.01^\circ \)) satisfy the constraint.

For the case \( n \geq 7 \), we show that any \( 0 < \epsilon < 0.4^\circ \) yields \( l_2 > \frac{1}{2} \), whence the constraint follows since \( \sin \beta \cos \beta = \frac{1}{2} \sin(2\beta) \leq \frac{1}{2} \) (the equality is an identity, the inequality uses \( \sin x \leq 1 \)).
Plugging our choice of $l_2$ into the definition of $l_P$ (3),

$$l_2 = l_P(\bar{\theta} - \epsilon/n) = \cos(\bar{\theta} - \epsilon/n) - \sqrt{l_1^2 - \sin^2(\bar{\theta} - \epsilon/n)}.$$  

(16)

Cosine is a decreasing function on $[0, \pi]$, so $\cos(\bar{\theta} - \epsilon/n) > \cos \bar{\theta} > \cos(\pi/2)$ given $0 < \bar{\theta} - \epsilon/n < \bar{\theta} < 2\pi/7$ (5) and $n \geq 7$.

Under the radical of (16), substituting $l_1 = \sin(\bar{\theta} + \epsilon)$ gives the expression $\sin^2(\bar{\theta} + \epsilon) - \sin^2(\bar{\theta} - \epsilon/n)$. Using the identity $\sin^2 x - \sin^2 y = \sin(x + y)\sin(x - y)$, this expression becomes $\sin(2\theta + \epsilon - \epsilon/n)\sin(\epsilon + \epsilon/n) \leq \sin(\epsilon + \epsilon/n) < \sin(2\epsilon) < \sin(0.8^\circ)$. The last two inequalities follow by noting that $0 < \epsilon + \epsilon/n < 2\epsilon < 0.8^\circ < \pi/2$, and sine is increasing on the interval $[0, \pi/2]$.

Using these bounds for the two terms in Equation (16),

$$l_2 > \cos \left(\frac{2\pi}{7}\right) - \sqrt{\sin(0.8^\circ)} \approx 0.505 > \frac{1}{2}.$$  

**Constraint** $\bar{\theta} + l_2 > 1$

Define function $f(\theta) = l_1 + l_P(\theta)$ on $[0, \beta]$. We know $l_P$ is a strictly increasing function on $[0, \beta]$, hence so is $f$. Furthermore, $f(0) = 1$, so $f(\bar{\theta}) > 1$ for $\theta \in (0, \beta]$.

From (3), we see $\bar{\theta} - \epsilon/n \in (0, \beta)$, so $f(\bar{\theta} - \epsilon/n) > 1$. By definition of $f$, this becomes $l_1 + l_P(\bar{\theta} - \epsilon/n) > 1$. Since $l_2 = l_P(\bar{\theta} - \epsilon/n)$, we obtain that $l_1 + l_2 > 1$ as desired.

**Constraint** $\alpha < \theta_m$

By definition, $\alpha = (2\pi - \beta)/(n - 1)$ (Equation 3). This shows $\alpha \geq 0$. Rewriting $2\pi$ as $n\bar{\theta}$, and $\beta$ as $\bar{\theta} + \epsilon$ (10), the equation for $\alpha$ becomes $\alpha = (n\bar{\theta} - \bar{\theta} - \epsilon)/(n - 1) = \bar{\theta} - \epsilon/(n - 1) < \bar{\theta} - \epsilon/n$. Combining all this with (15), we find

$$0 < \alpha < \bar{\theta} - \epsilon/n < \bar{\theta} < \beta < \pi/2.$$  

(17)

From (17) we see that $\alpha \in (0, \pi)$. By definition (Equation 10), $\theta_m$ is also in $(0, \pi)$. Since cosine is decreasing on this interval, the constraint $\alpha < \theta_m$ holds if, and only if, $\cos \alpha > \cos \theta_m$. Using the definition of $\theta_m$ (Equation 10), this latter inequality becomes $2l_2 \cos \alpha > 1 - l_1^2 + l_2^2$. We collect the terms in $l_2$ to one side, $l_2^2 - 2l_2 \cos \alpha < l_1^2 - 1$, and complete the square to get

$$(l_2 - \cos \alpha)^2 < l_1^2 - \sin^2 \alpha.$$  

Since $l_1 = \sin \beta$ (by definition of $\beta$, Equation 3), the right hand side can be written as $\sin^2 \beta - \sin^2 \alpha$, which is positive since $\alpha < \beta$ by (17). Since both sides of the inequality are positive, we can take square roots which leads to

$$|l_2 - \cos \alpha| < \sqrt{l_1^2 - \sin^2 \alpha},$$  

so

$$-\sqrt{l_1^2 - \sin^2 \alpha} < l_2 - \cos \alpha < \sqrt{l_1^2 - \sin^2 \alpha},$$
and we deduce that \( l_2 \) (which equals \( l_P(\bar{\theta} - \epsilon/n) \)) must satisfy
\[
\cos \alpha - \sqrt{l_1^2 - \sin^2 \alpha} < l_P(\bar{\theta} - \epsilon/n) < \cos \alpha + \sqrt{l_1^2 - \sin^2 \alpha}.
\] (18)

Comparing the left inequality of this with the definition of \( l_P \) \( (5) \), we see that the former can be written \( l_P(\alpha) < l_P(\bar{\theta} - \epsilon/n) \). From \( (17) \) we note that \( \alpha < \bar{\theta} - \epsilon/n \) and both quantities are in the range \([0, \beta]\). The increasing property of \( l_P \) ensures that the left inequality of \( (18) \) is satisfied.

For the upper bound, note that by \( (15) \), \( \bar{\theta} - \epsilon/n < \bar{\theta} \) and both quantities are in the range \([0, \beta]\). The increasing property of \( l_P \) ensures that \( l_P(\bar{\theta} - \epsilon/n) < l_P(\bar{\theta}) \).

By the definition of \( l_P \) \( (3) \), \( l_P(\bar{\theta}) < \cos \bar{\theta} \). Given \( 0 < \alpha < \bar{\theta} < \pi/2 \) \( (17) \), the decreasing nature of cosine on this interval ensures \( \cos \bar{\theta} < \cos \alpha \). Putting this together, we find \( l_P(\bar{\theta} - \epsilon/n) < \cos \alpha \), so the upper bound of Inequality \( (18) \) is satisfied.

\( \square \)

References

[1] T. Biedl, E. Demaine, M. Demaine, S. Lazard, A. Lubiw, J. O’Rourke, M. Overmars, S. Robbins, I. Streinu, G. Toussaint, and S. Whitesides. Locked and unlocked polygonal chains in 3d. In 10th Annual ACM-SIAM Symposium on Discrete Algorithms, pages 866–867, Jan. 1999.

[2] T. Biedl, E. Demaine, M. Demaine, S. Lazard, A. Lubiw, J. O’Rourke, S. Robbins, I. Streinu, G. Toussaint, and S. Whitesides. On reconfiguring tree linkages: Trees can lock. In Proceedings of the Tenth Canadian Conference on Computational Geometry, pages 4–5. McGill University, Montreal, Quebec, Canada, Aug. 1998. (Extended Abstract).

[3] T. C. Biedl, E. D. Demaine, S. Lazard, S. M. Robbins, and M. A. Soss. Convexifying monotone polygons. In Tenth Annual International Symposium on Algorithms and Computation, volume 1741 of Lecture Notes in Computer Science, pages 415–424, 1999.

[4] T. C. Biedl, E. D. Demaine, M. A. Soss, and G. T. Toussaint. Straightening visible chains under constraints. Technical Report CS-99-08, Department of Computer Science, University of Waterloo, Waterloo, Ontario, Canada, 1999.

[5] J. Canny. The Complexity of Robot Motion Planning. ACM Doctoral Dissertation Award Series. MIT Press, Cambridge, MA, 1988.

[6] R. Cocan and J. O’Rourke. Polygonal chains cannot lock in 4d. In Proceedings of the Eleventh Canadian Conference on Computational Geometry, pages 5–8. University of British Columbia, Vancouver, B.C., Canada, Aug. 1999. (Extended Abstract).
[7] R. Connelly, E. D. Demaine, and G. Rote. Straightening polygonal arcs and convexifying polygonal cycles. In *Symposium on Foundations of Computer Science*, November 2000. In press.

[8] E. D. Demaine and M. L. Demaine. Computing extreme origami bases. Technical Report CS-97-22, Department of Computer Science, University of Waterloo, Waterloo, Ontario, Canada, May 1997.

[9] H. Everett, S. Lazard, S. Robbins, H. Schröder, and S. Whitesides. Convexifying star-shaped polygons. In *Proceedings of the Tenth Canadian Conference on Computational Geometry*, pages 2–3. McGill University, Montreal, Quebec, Canada, Aug. 1998. (Extended Abstract).

[10] J. Hopcroft, D. Joseph, and S. Whitesides. Movement problems for 2-dimensional linkages. *SIAM J. Comput.*, 13:610–629, 1984.

[11] J. Hopcroft, D. Joseph, and S. Whitesides. On the movement of robot arms in 2-dimensional bounded regions. *SIAM J. Comput.*, 14(2):315–333, 1985.

[12] V. Kantabutra. Motions of a short-linked robot arm in a square. *Discrete Comput. Geom.*, 7:69–76, 1992.

[13] V. Kantabutra. Reaching a point with an unanchored robot arm in a square. *International Journal of Computational Geometry and Applications*, 7(6):539–550, 1997.

[14] V. Kantabutra and S. R. Kosaraju. New algorithms for multilink robot arms. *Journal of Computer and System Sciences*, 32:136–153, 1986.

[15] M. Kapovich and J. Millson. On the moduli spaces of polygons in the Euclidean plane. *Journal of Differential Geometry*, 42(1):133–164, 1995.

[16] R. Kirby. Problems in low-dimensional topology, 1996.

[17] J. U. Korein. *A Geometric Investigation of Reach*. ACM distinguished dissertations series. MIT Press, Cambridge MA, USA, 1985.

[18] W. J. Lenhart and S. H. Whitesides. Turning a polygon inside-out. In *Proc. 3rd Canad. Conf. Comput. Geom.*, pages 66–69, Aug. 1991.

[19] W. J. Lenhart and S. H. Whitesides. Reconfiguration with line tracking motions. In *Proc. 4th Canad. Conf. Comput. Geom.*, pages 198–203, 1992.

[20] W. J. Lenhart and S. H. Whitesides. Reconfiguring simple polygons. Technical Report SOCS-93-3, School of Computer Science, McGill University, Canada, March 1993.

[21] W. J. Lenhart and S. H. Whitesides. Reconfiguring closed polygonal chains in Euclidean d-space. *Discrete Comput. Geom.*, 13:123–140, 1995.
[22] J. O’Rourke. Computational geometry column 39. *International Journal of Computational Geometry and Applications*, 2000. In press.

[23] N. Pei. *On the Reconfigurations and Reachability of Chains*. PhD thesis, McGill University, 1996.

[24] N. Pei and S. Whitesides. On the reachable regions of chains. In *Proceedings of the Eighth Canadian Conference on Computational Geometry*, pages 161–166. Carleton University, Ottawa, Ontario, Canada, Aug. 1996.

[25] N. Pei and S. Whitesides. On the reconfiguration of chains. In J.-Y. Cai and C. Wong, editors, *Computing and Combinatorics, Proceedings of the Second Annual International Conference, COCOON ’96*, volume 1090 of *Lecture Notes in Computer Science*, pages 381–390. Springer-Verlag, June 1996.

[26] N. Pei and S. Whitesides. On folding rulers in regular polygons. In *Proceedings of the Ninth Canadian Conference on Computational Geometry*, pages 11–16. Queen’s University, Kingston, Ontario, Canada, Aug. 1997.

[27] J. T. Schwartz and M. Sharir. On the “piano movers” problem II: general techniques for computing topological properties of real algebraic manifolds. *Advances in Applied Mathematics*, 4:298–351, 1983.

[28] I. Streinu. A combinatorial approach to planar non-colliding robot arm motion planning. In *Symposium on Foundations of Computer Science*, November 2000. In press.

[29] I. Suzuki and M. Yamashita. Designing multi-link robot arms in a convex polygon. *International Journal of Computational Geometry and Applications*, 6:461–486, 1996.

[30] M. van Kreveld, J. Snoeyink, and S. Whitesides. Folding rulers inside triangles. *Discrete Comput. Geom.*, 15:265–285, 1996.

[31] S. H. Whitesides. Algorithmic issues in the geometry of planar linkage movement. *The Australian Computer Journal*, pages 42–50, May 1992.