ASSIGNMENT 3

Configuration Space
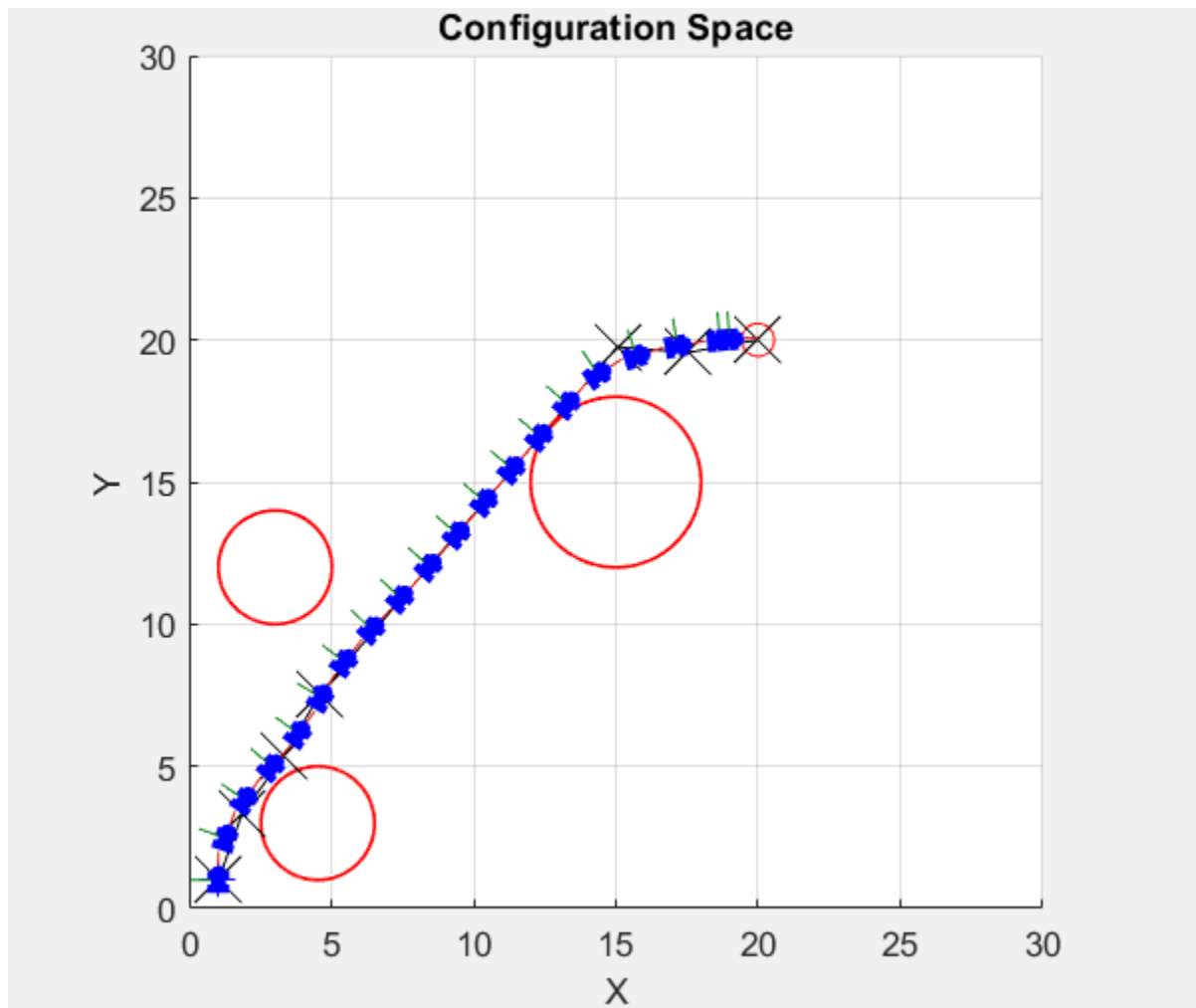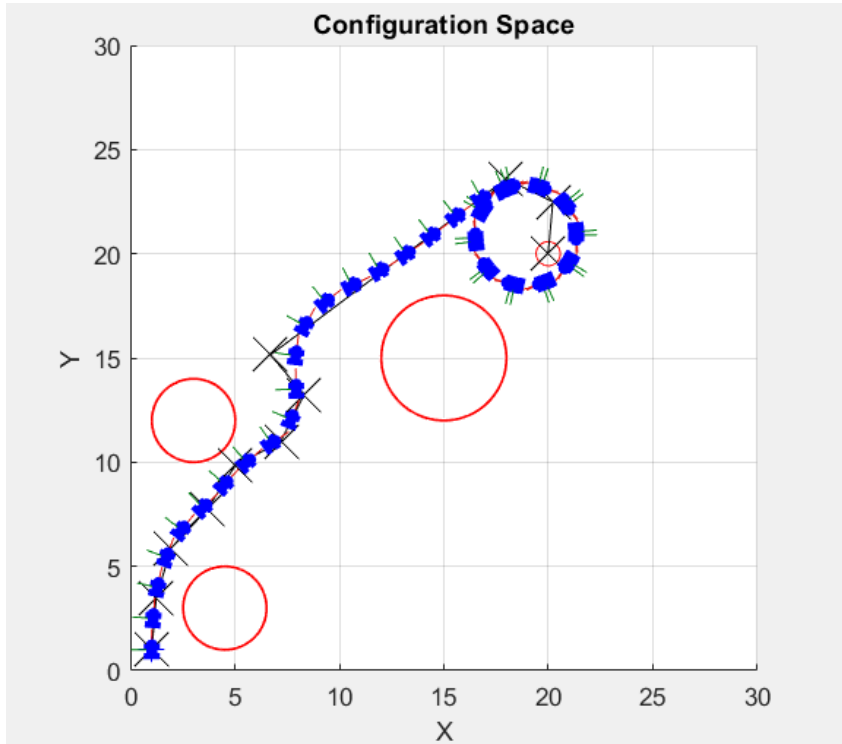
Trajectory generation: using an ode solver to generate the pose and the time for each waypoint using the function. The ode solver generate the x_dot, y_dot and time for the given x and y points using the inbuilt function `exampleHelperMobileRobotController`.

Reference:
https://in.mathworks.com/help/robotics/ug/simulate-different-kinematic-models-for-mobile-robots.html