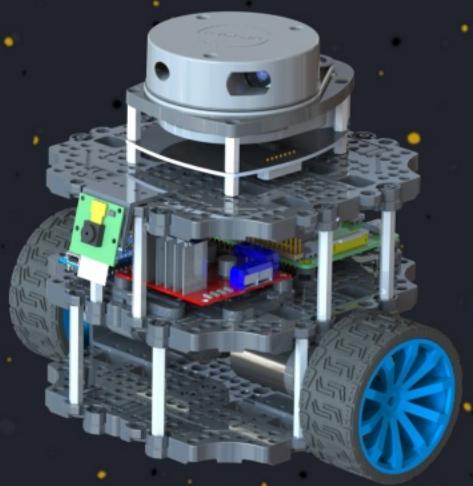


# Locomotion

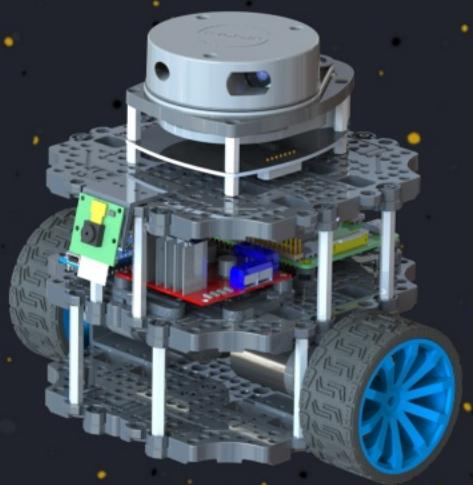






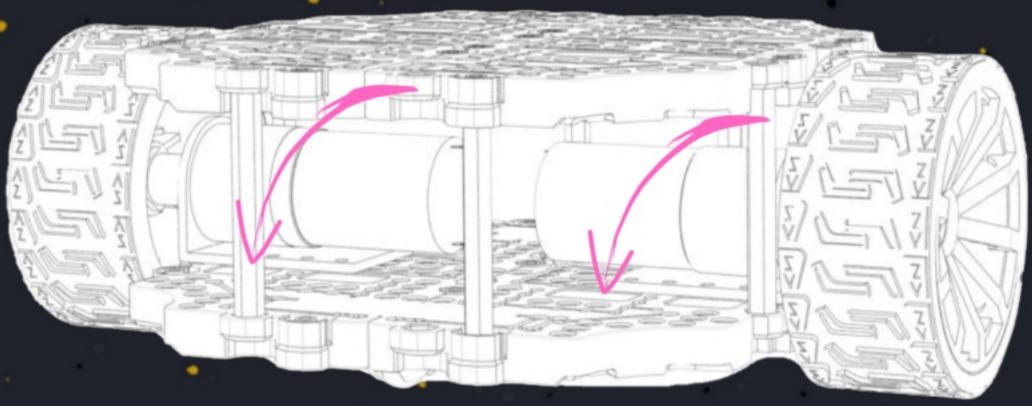


# Locomotion

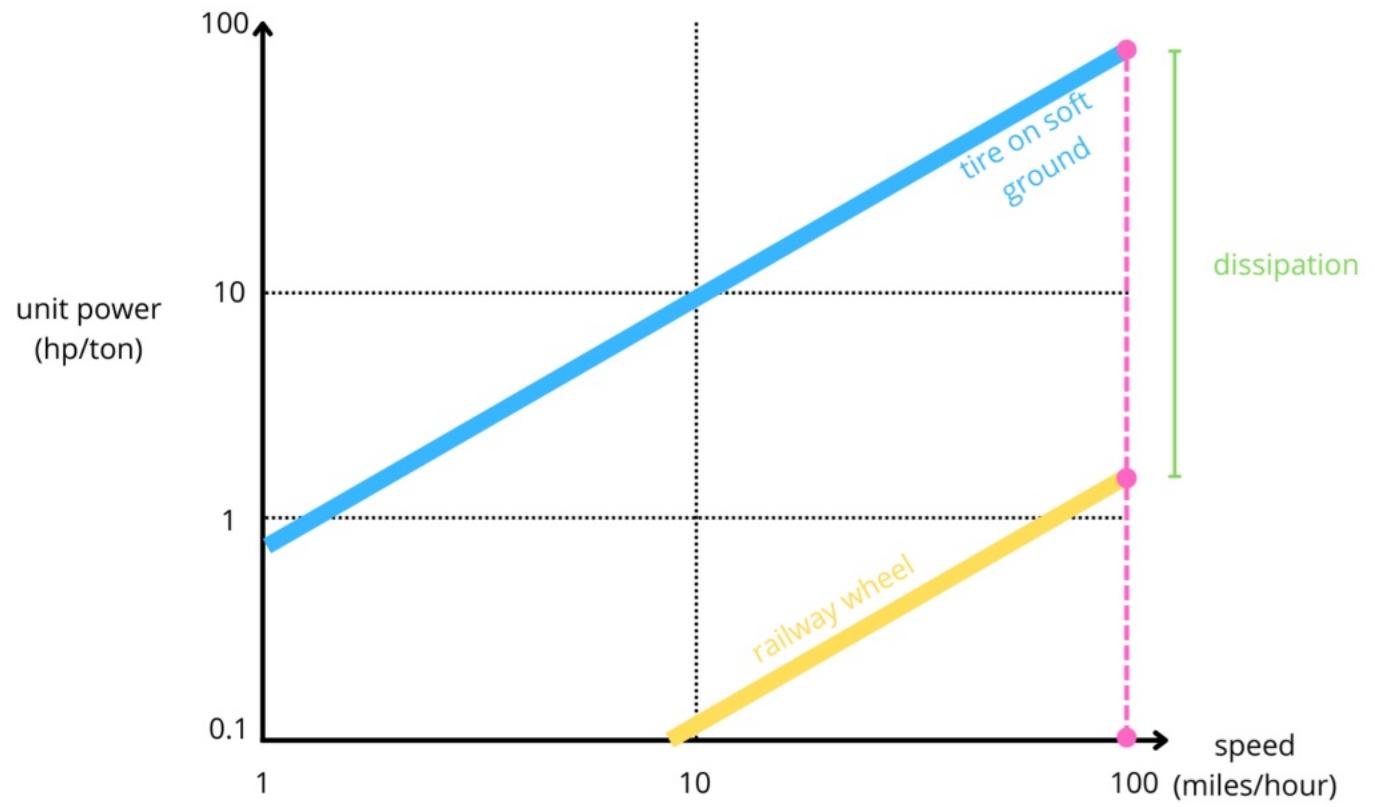




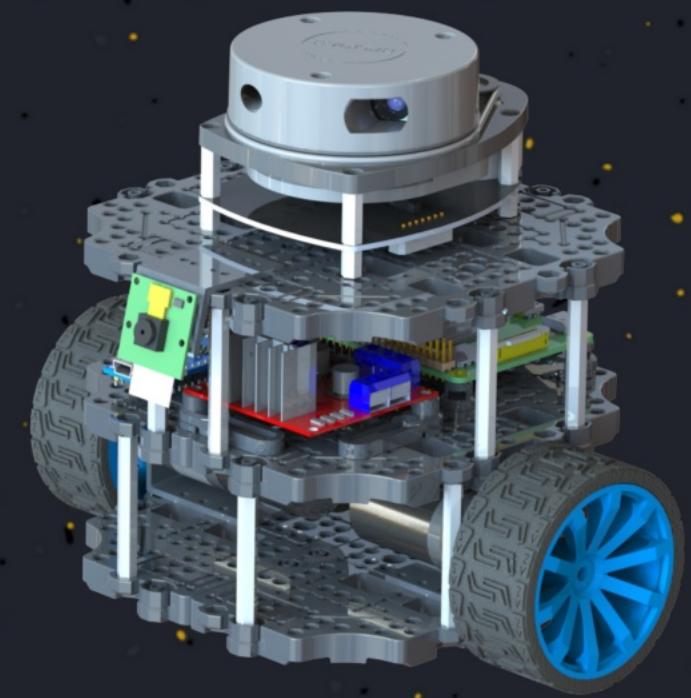
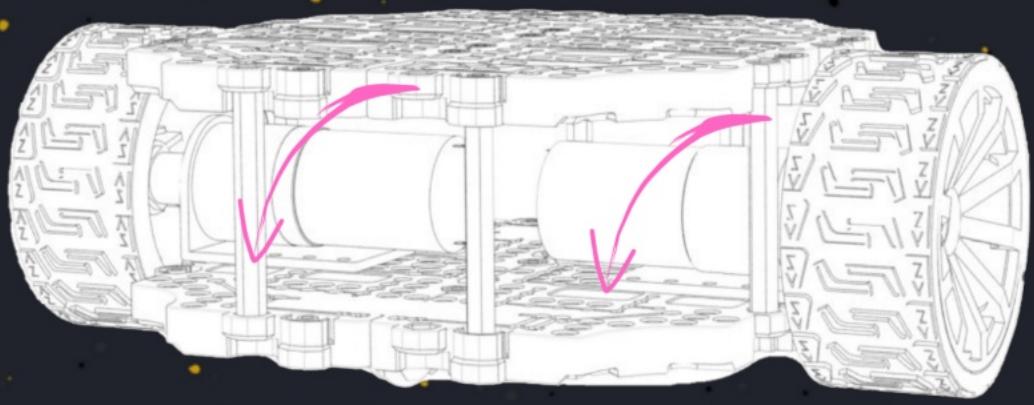


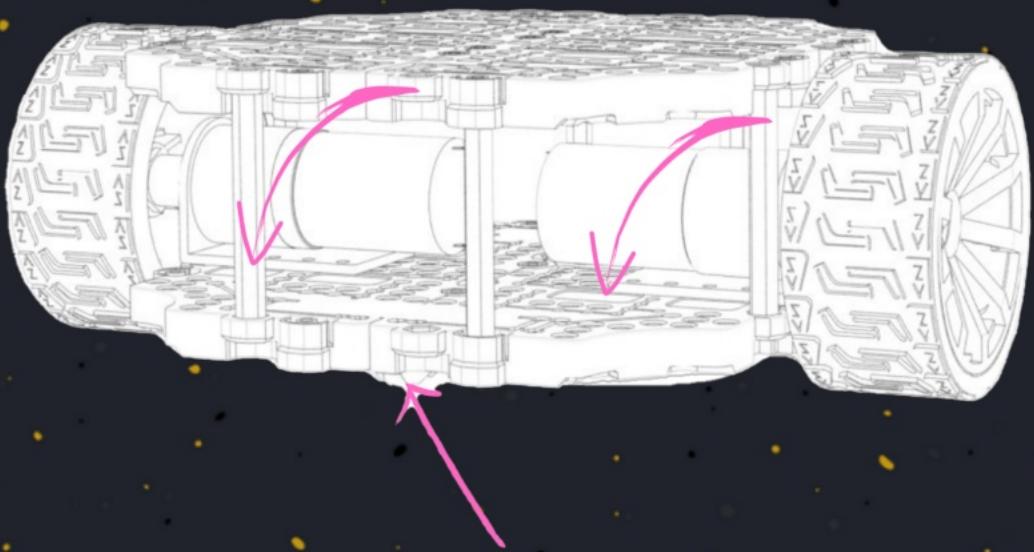






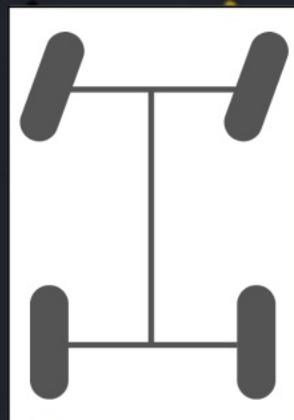








Differential Drive



Ackerman Drive



Omnidirectional Drive

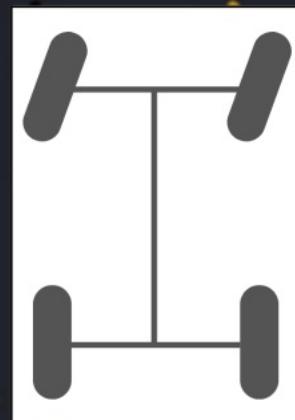


# Differential Drive





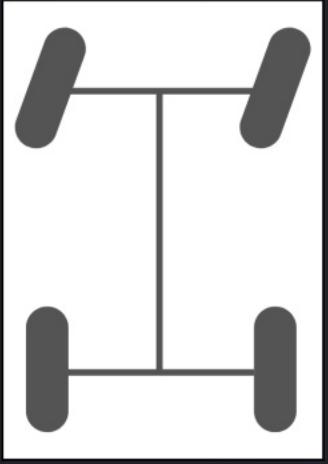
Differential Drive



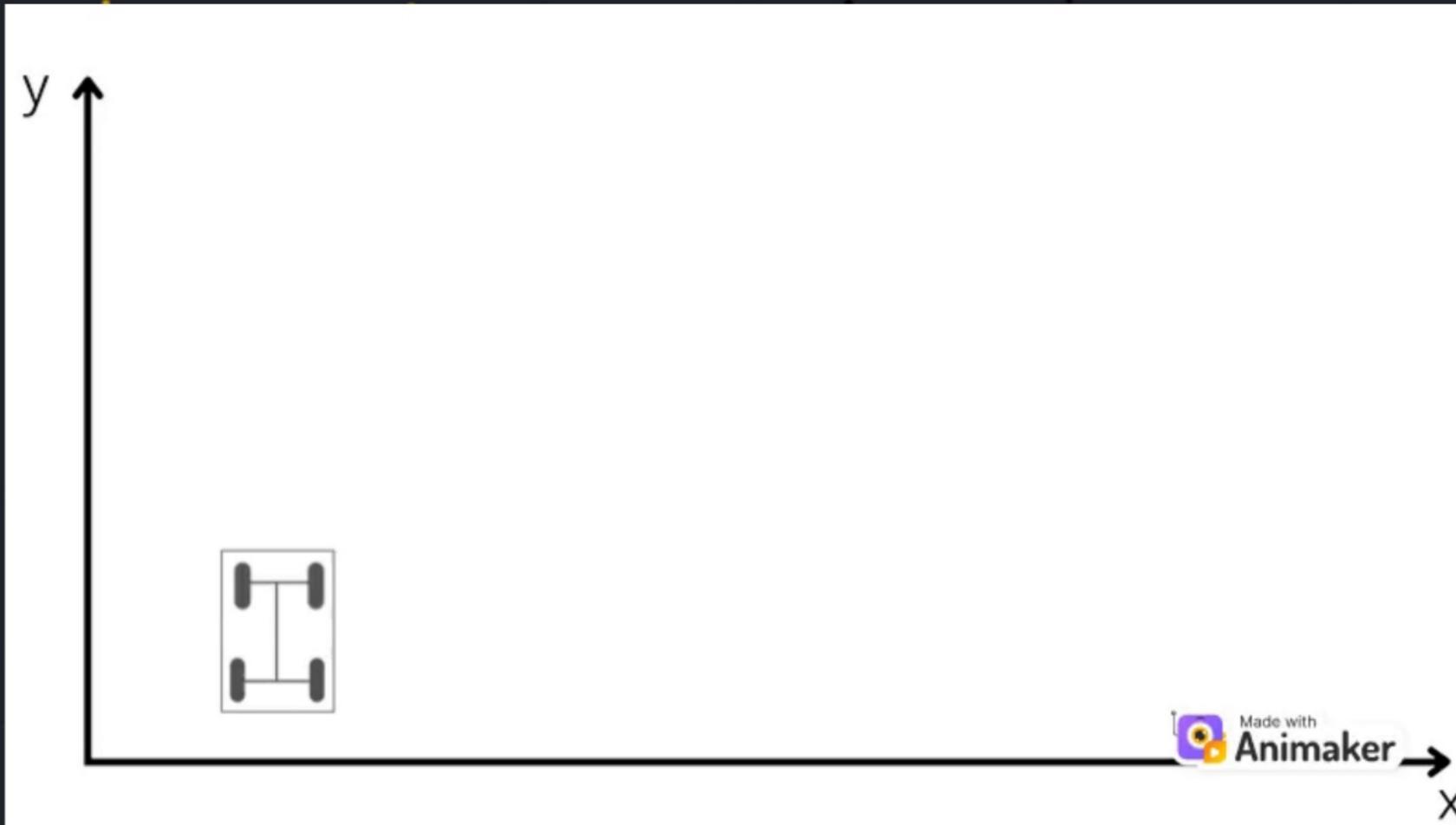
Ackerman Drive



Omnidirectional Drive



# Ackerman Drive





Differential Drive



Ackerman Drive



Omnidirectional Drive



# Omnidirectional Drive





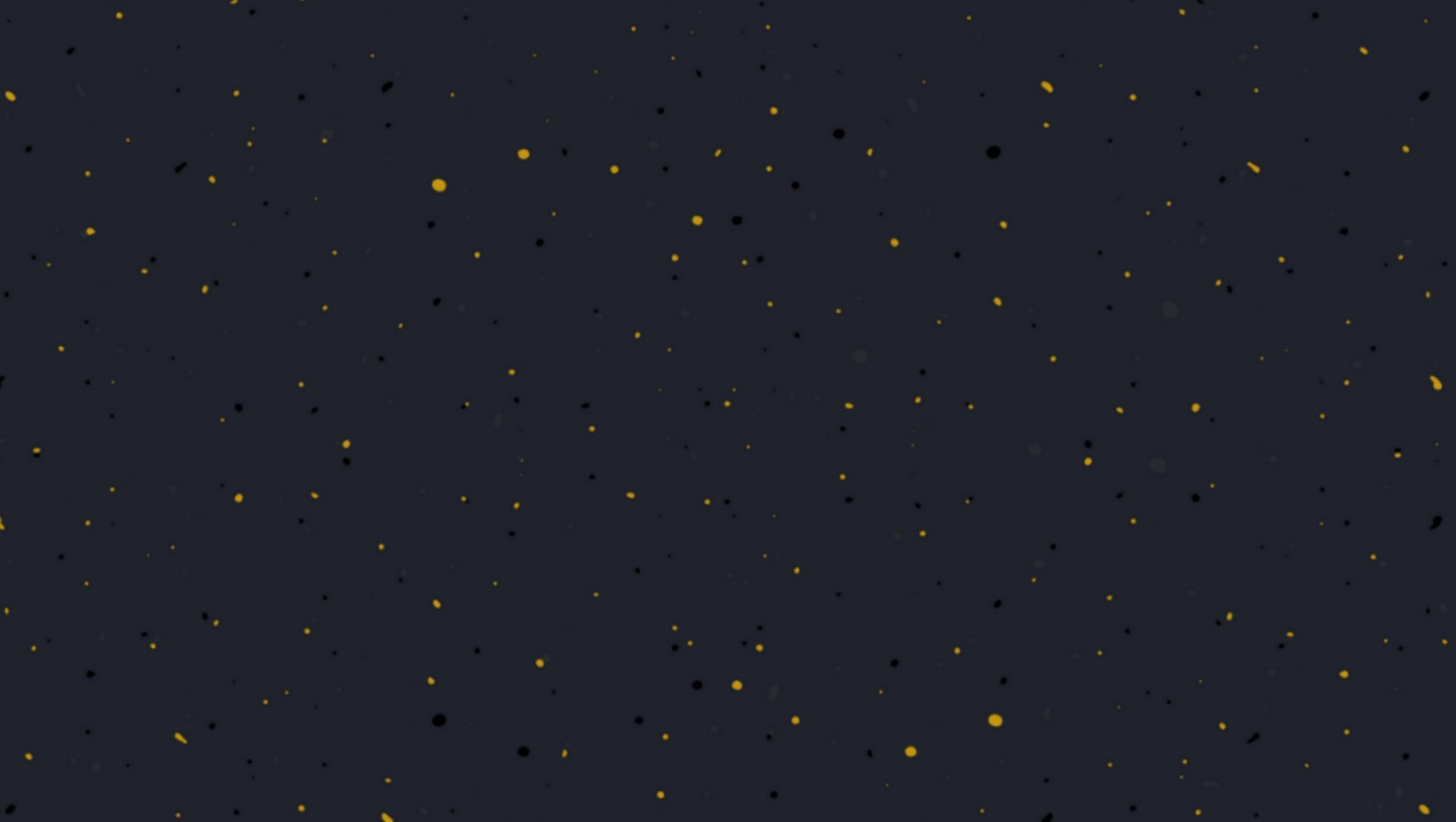
Differential Drive

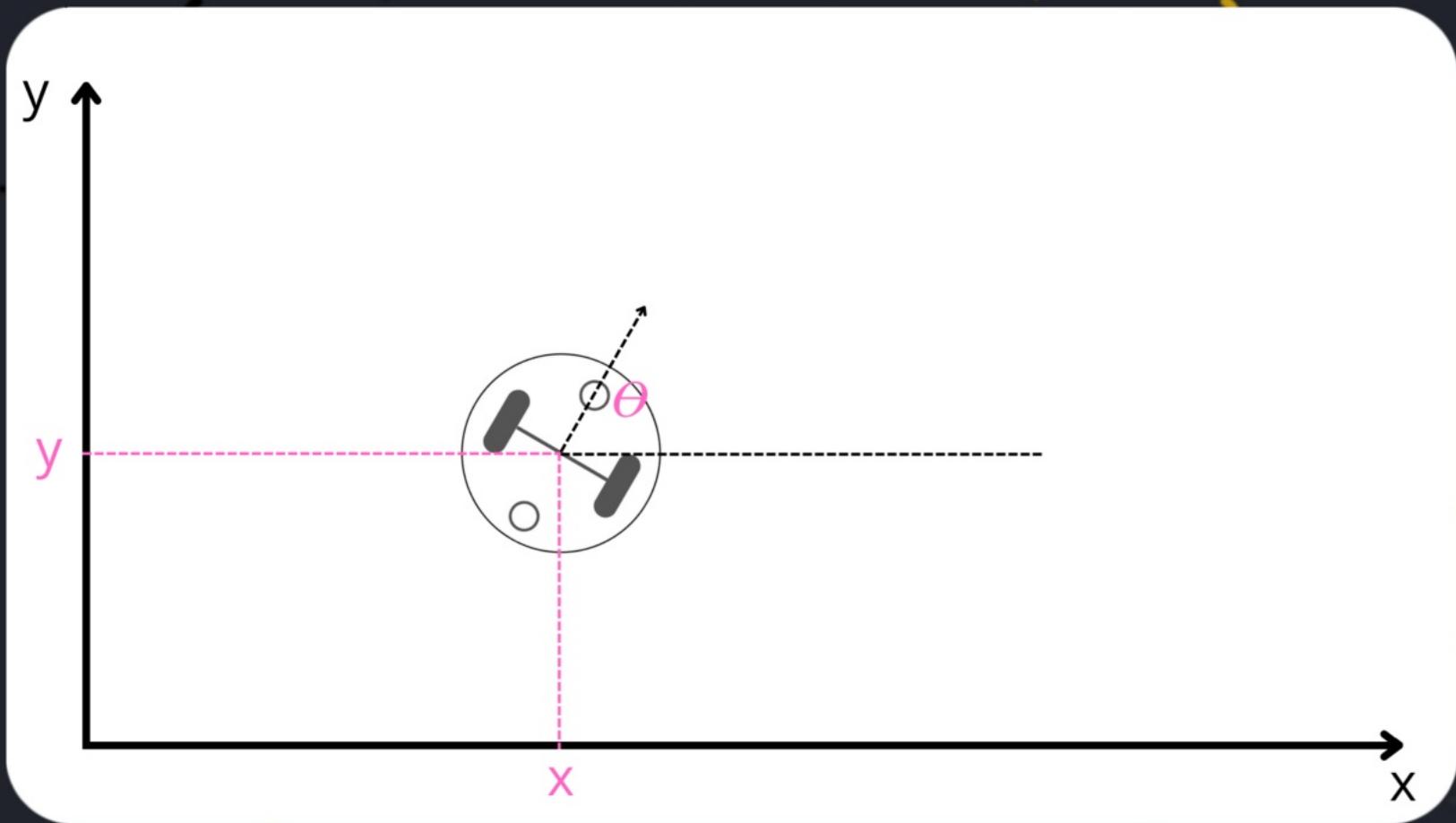


Ackerman Drive



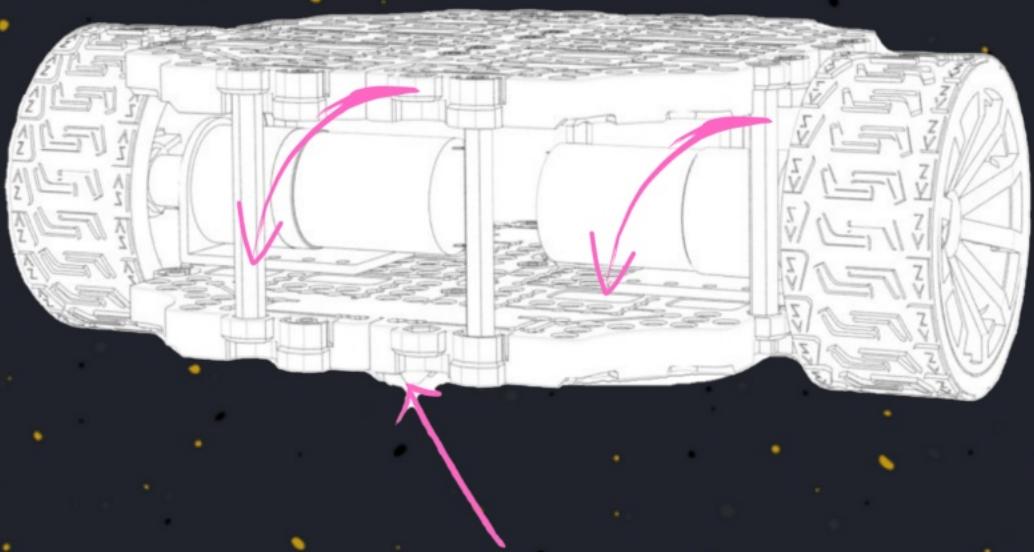
Omnidirectional Drive



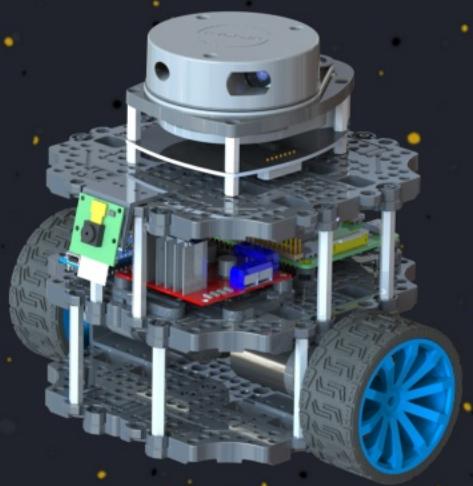


State Space ( $x$ ,  $y$ , theta)





# Locomotion





# Locomotion

