Switching: Position Regulation and State Feedback with Approximate Linearization x-axis Behaviour Robot 1 Walls Desired Trajectory 10 20 30 50 60 70 t [s] 19.78 oo[±] Robot 2 Walls Desired Trajectory 20 50 70 10 30 60 t [s] 19.78 S Robot 3 Walls Desired Trajectory 70 20 10 30 60 t [s]