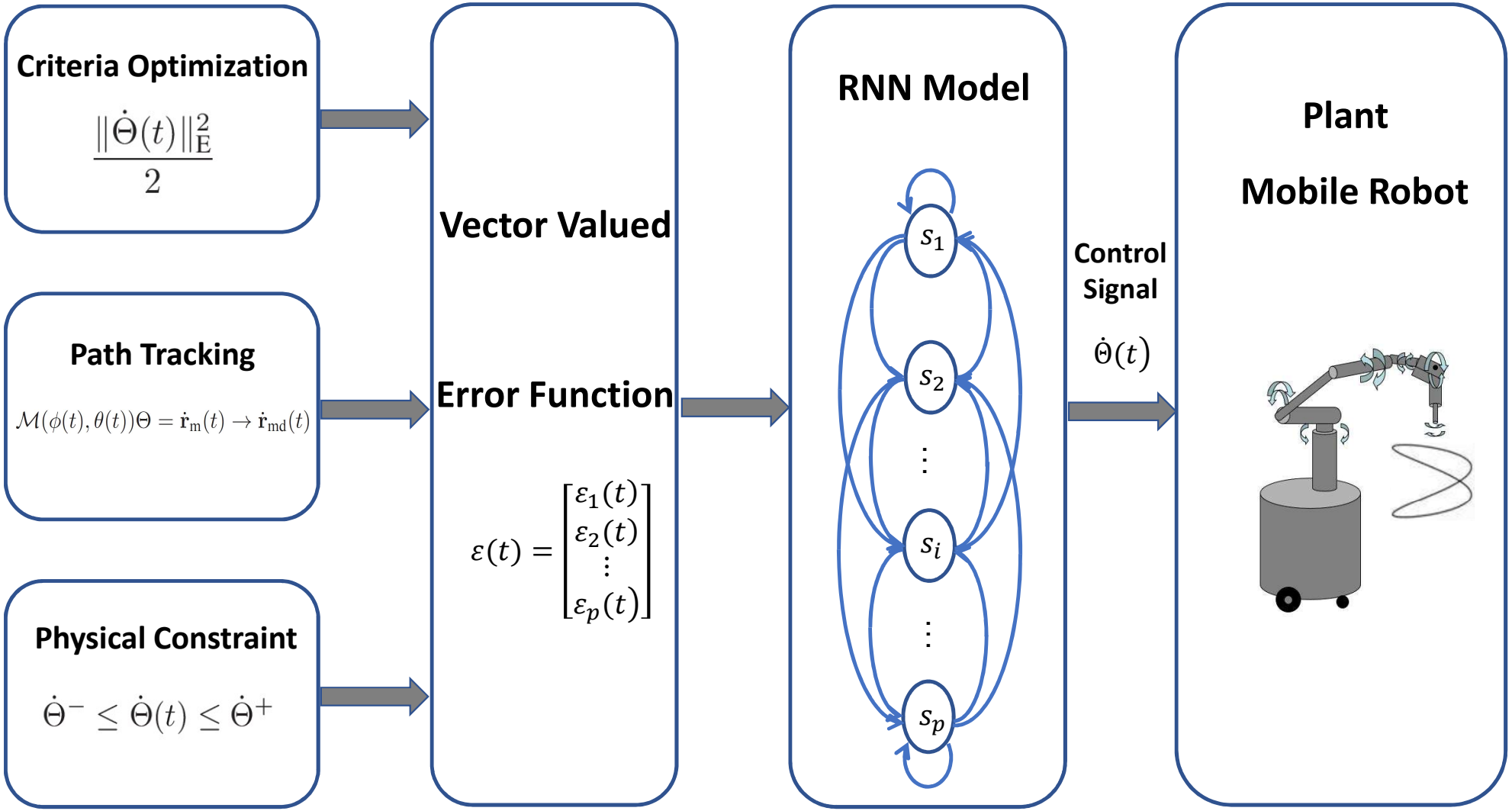
Criteria Optimization
$\frac{\|\dot{\Theta}(t)\|_{\mathrm{E}}^2}{2}$
Path Tracking
$\mathcal{M}(\phi(t),\theta(t))\Theta = \dot{\mathrm{r}}_{\mathrm{m}}(t) \to \dot{\mathrm{r}}_{\mathrm{md}}(t)$
Physical Constraint
$\dot{\Theta}^- \leq \dot{\Theta}(t) \leq \dot{\Theta}^+$
Vector Valued
Error Function
$\varepsilon(t) = \begin{bmatrix} \varepsilon_1(t) \\ \varepsilon_2(t) \\ \vdots \\ \varepsilon_p(t) \end{bmatrix}$
RNN Model
s_1
s_2
s_i
s_p
Control Signal
$\dot{\Theta}(t)$
Plant
Mobile Robot