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code style black

## Purpose

A simple simulator to explore direct and inverse kinematics for a differential wheeled robot

```
Simple Robot Simulator
q; quit, tab: next mode, mouse; goal position, arrows: wheel speed control, space; speed 0 to wheels, a: artist toggle
Time: 145.43
Mode: WHEEL_CONTROL, artist: False
Left wheel speed: 0.00 mm/s
Right wheel speed: 0.00 mm/s
Linear speed: 0.00 mm/s
Angular speed: 0.000 rad/s
```

## Install

Tested with Python 3.6 but should work as long as pygame is installed.

```
pip install pygame
```

## Usage

```
python main.py
```

## Keys:

q: quit

tab: next mode

mouse: goal position

arrows: wheel speed control space: speed 0 to wheels

a: artist toggle

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