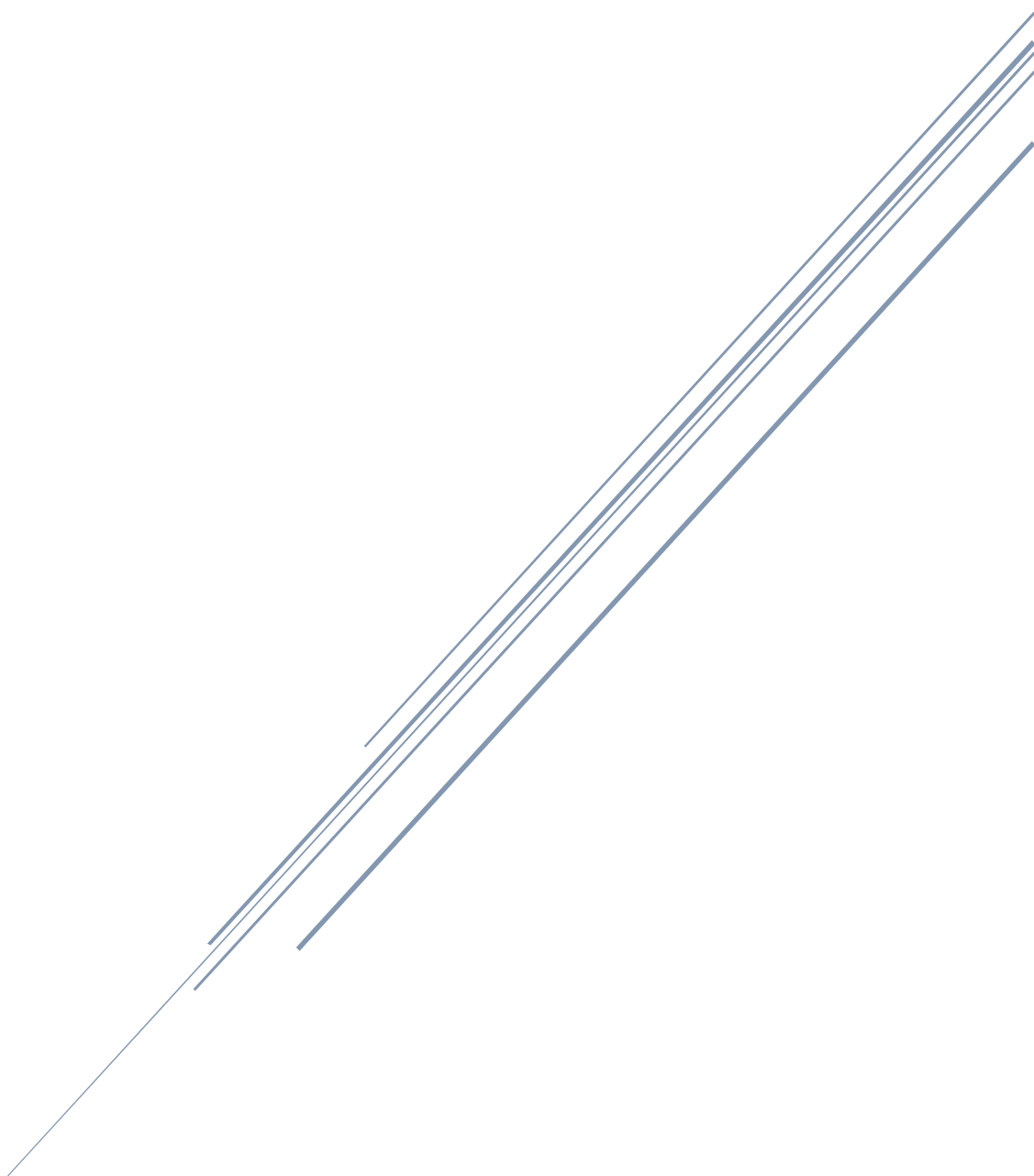


MEMORIA 4 MEC

17/04/2019

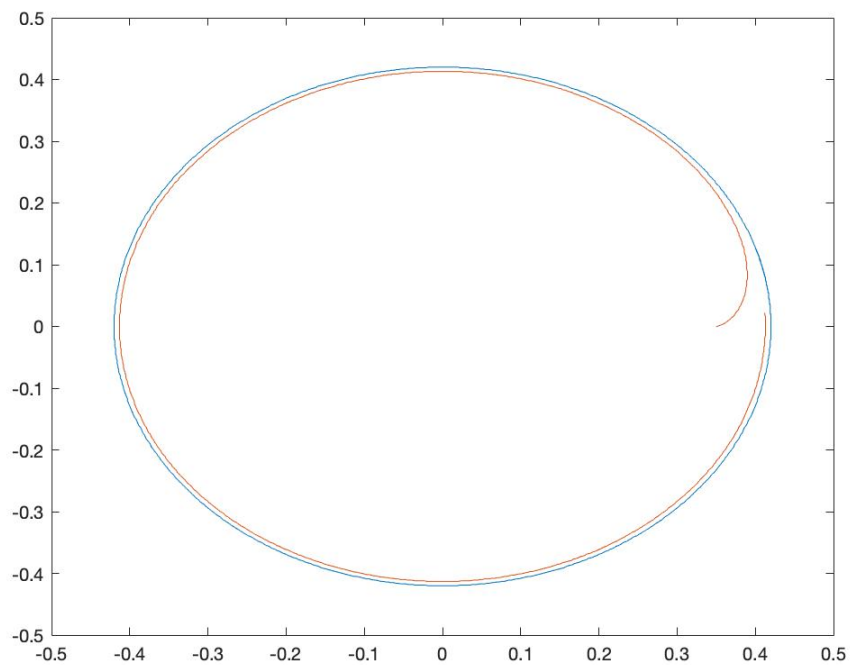


Sergi Sanz Carreres
Adrian Tendero Lara

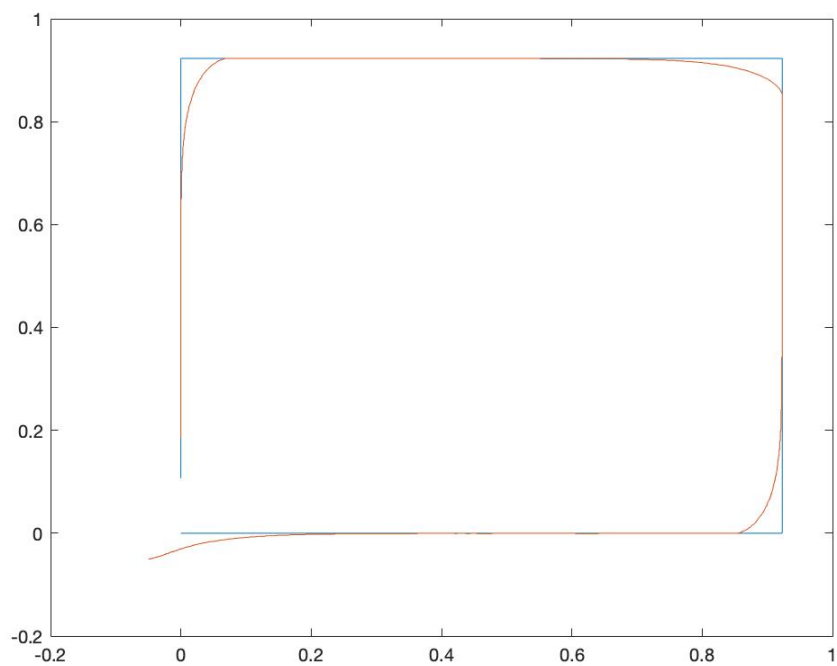
Figuras con la respuesta del robot

Posición de referencia y real del robot

Circulo:

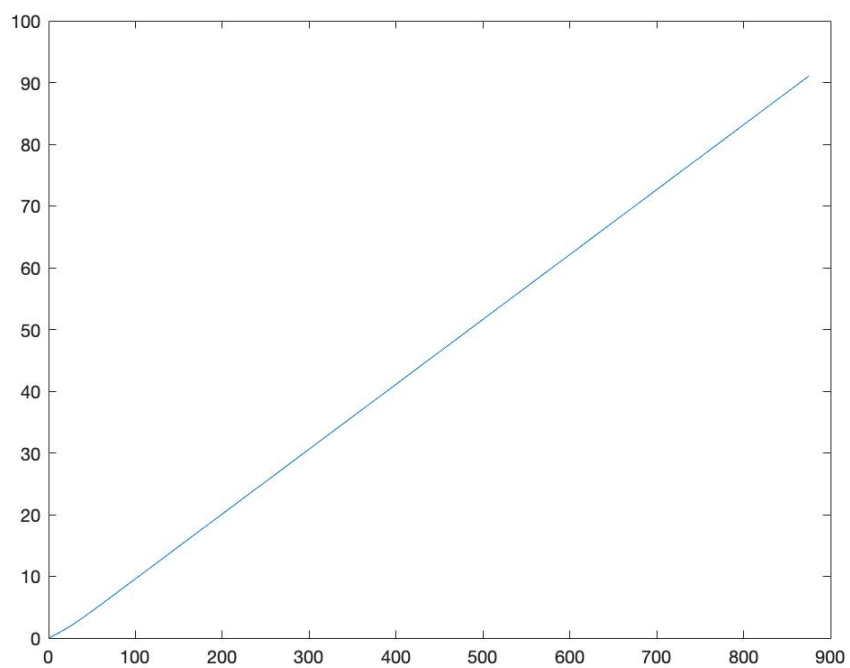


Cuadrado:

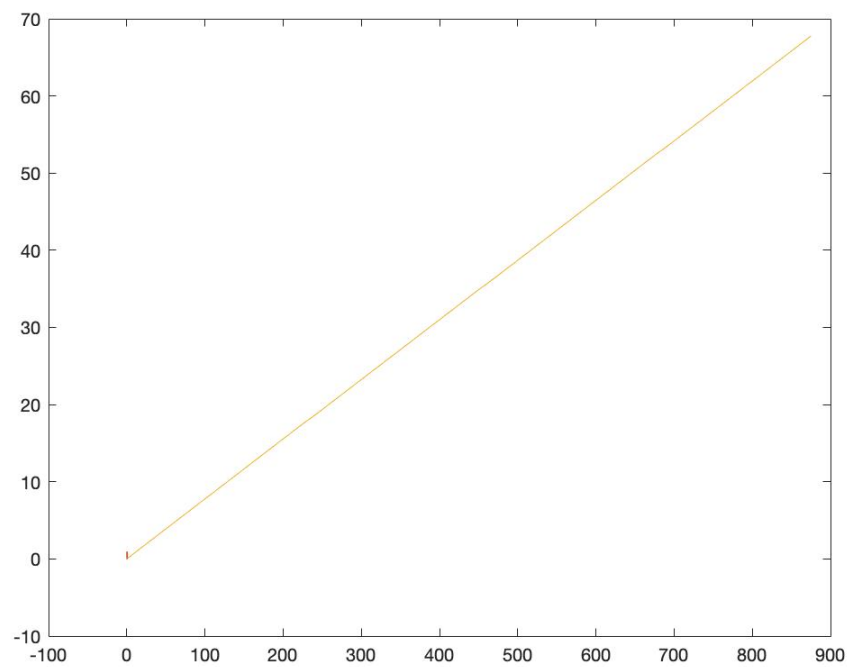


Índices integral error cuadrático posición robot

Círculo:



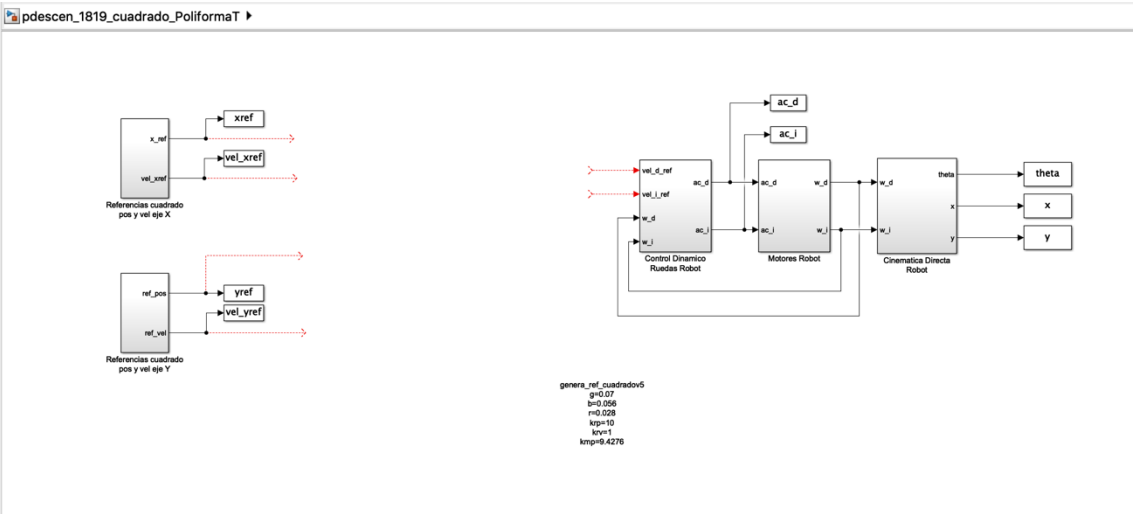
Cuadrado:



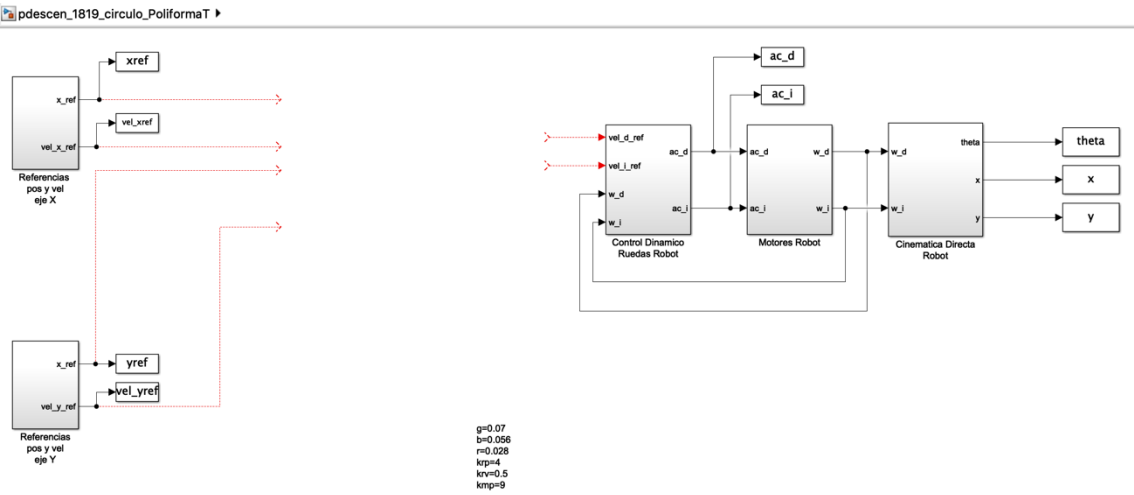
Opcional:

Esquemas Simulink:

Cuadrado:

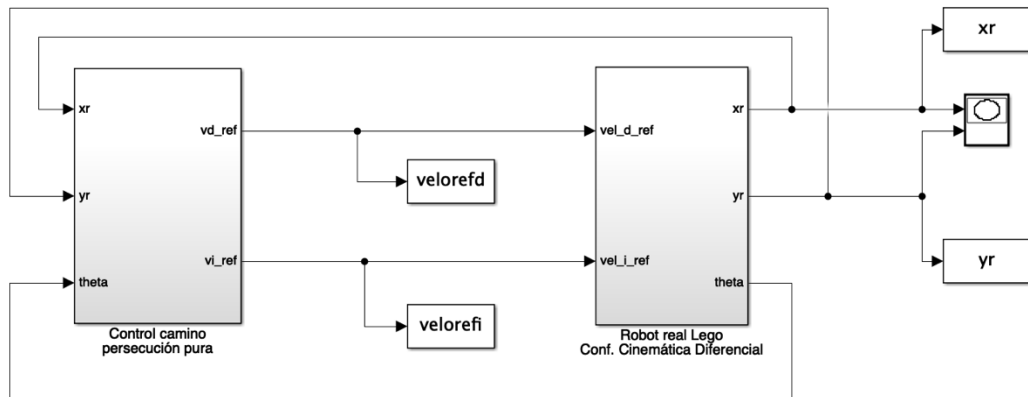


Circulo



Control persecución pura

control_ppura ▶



load path_ppura

$x_camino=x_path2$
 $x_camino=x_path3$
 $x_camino=x_path4$

$y_camino=y_path2$
 $y_camino=y_path3$
 $y_camino=y_path4$

Dis_fija=1

$V=0.3$

Control dinámico
 $kmp=9.4276$

Radio ruedas
 $r=0.028$

Sep. ruedas/2
 $b=0.0589$