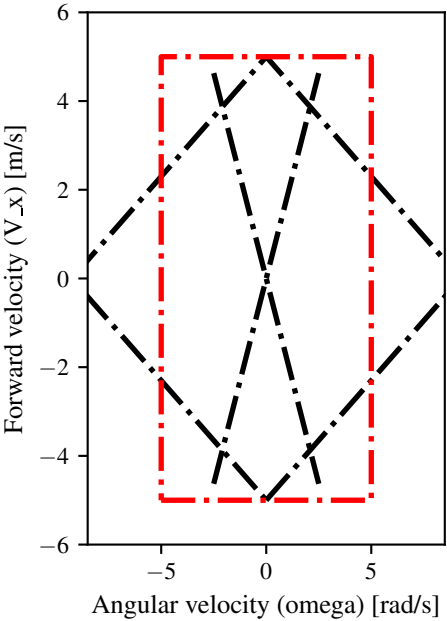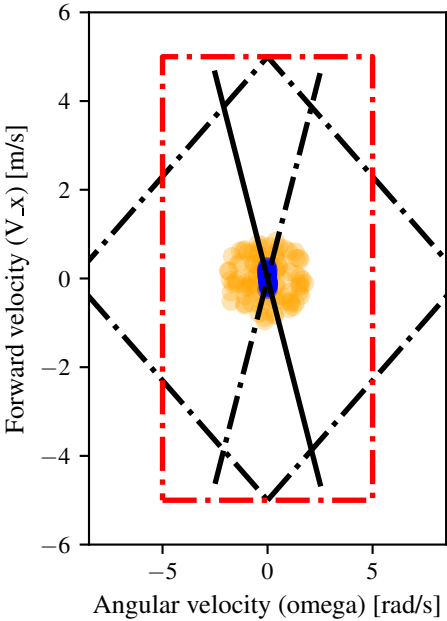# Roboticist williamhardy with a maximum linear sampling speed of 1.0 m/s
Cmd vs steady-state results for all_types_of_terrain

Body vel on avide

Forward velocity (V_x) [m/s]

Angular velocity (omega) [rad/s]

Forward velocity (V_x) [m/s]

Angular velocity (omega) [rad/s]

Command

Mean of body steady-state speed

Mean of wheel steady-state speed

—— vehicle limits

- - - r = inf :straight line

.... r = 0 : Turning on spot
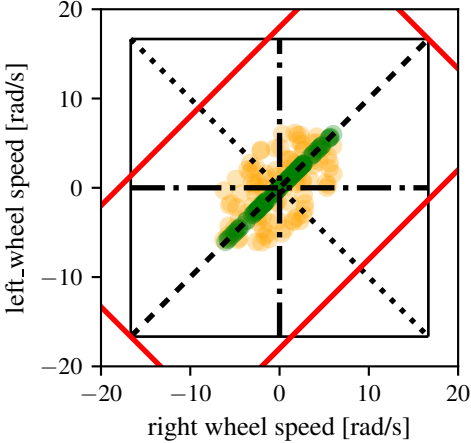
$\frac{b}{2} < r < i$

$\frac{-b}{2} < r <$

$-inf < r$

Wheels vel on avide

left_wheel speed [rad/s]

right wheel speed [rad/s]

Graph analyzer helper

left_wheel speed [rad/s]

right wheel speed [rad/s]

$r = \frac{b}{2}$

$r = 0$

$r = \frac{-b}{2}$

$r = \frac{-b}{2}$

$r = 0$

$r = \frac{b}{2}$