Pregunta 1.

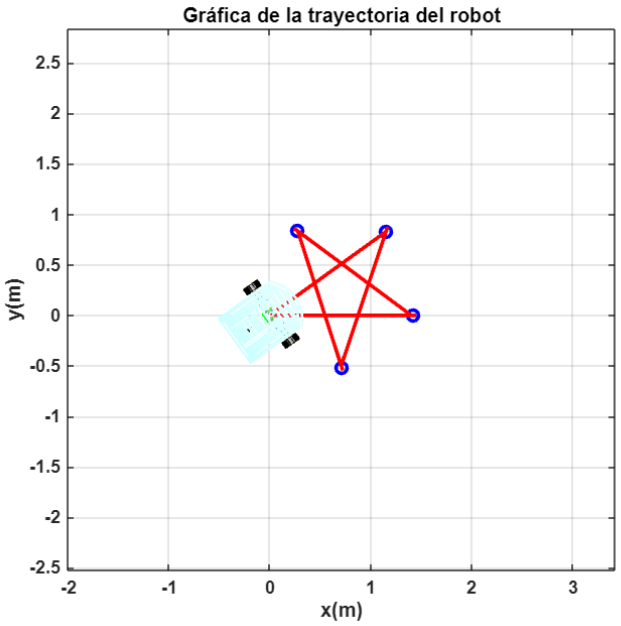
a) Pose del robot de acuerdo con las velocidades de cada paso

Paso 1	1.4	0.0	0.0°
Paso 2	1.4	0.0	144°
Paso 3	0.3	0.8	144°
Paso 4	0.3	0.8	288°
Paso 5	0.7	-0.5	288°
Paso 6	0.7	-0.5	432°
Paso 7	1.2	0.8	432°
Paso 8	1.2	0.8	575°
Paso 9	0.0	0.0	575°
Paso 10	0.0	0.0	719°

b) Pose final

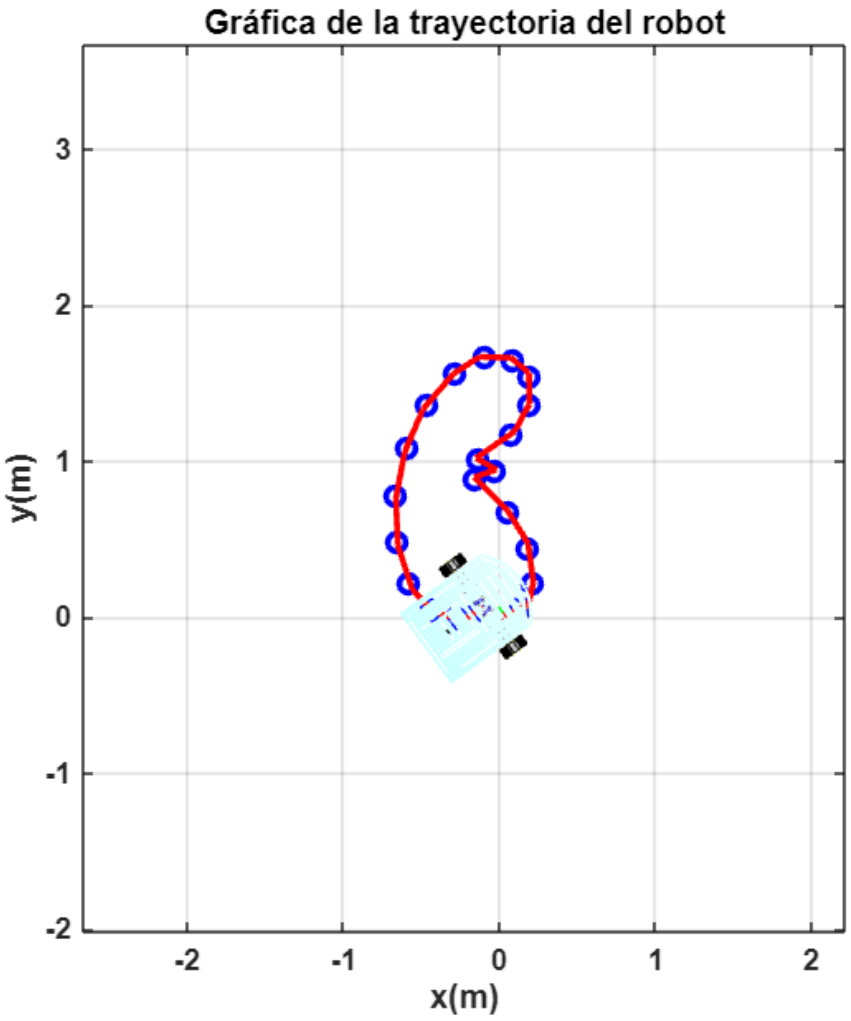
$$pose\ final = \begin{bmatrix} 0.0 \\ 0.0 \\ 719° \end{bmatrix}$$

c) Simulación de la trayectoria



Pregunta 2

a) Tabla en hoja
b) Gráfica de la trayectoria



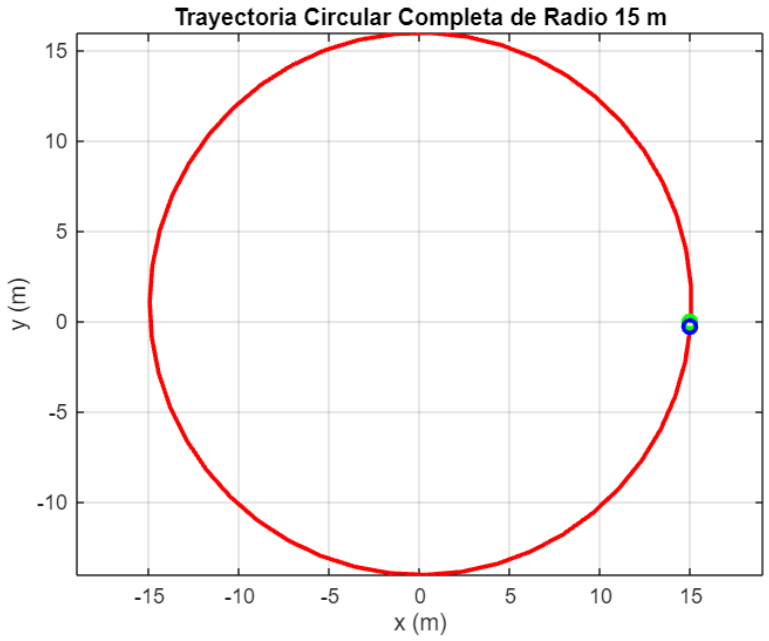
Pregunta 3

a) Tabla

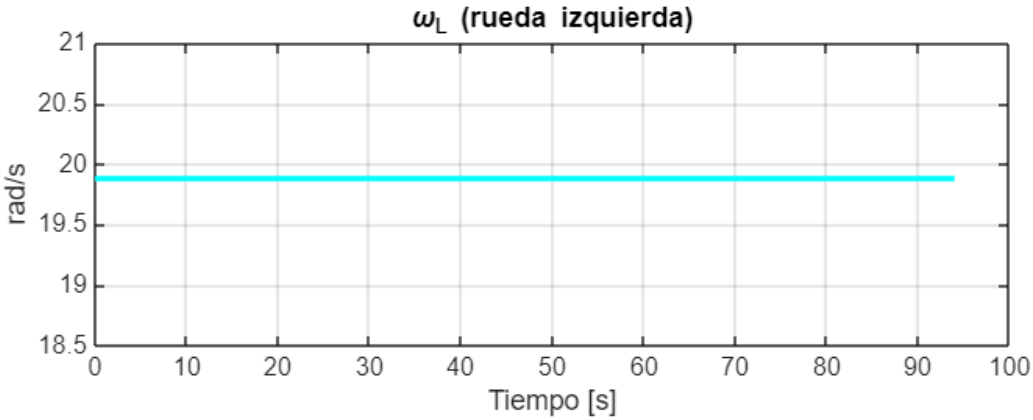
	Tiempo_s	w_R_rad_s	w_L_rad_s
1	0	20.1200	19.8800
2	2	20.1200	19.8800
3	4	20.1200	19.8800
4	6	20.1200	19.8800
5	8	20.1200	19.8800
6	10	20.1200	19.8800
7	12	20.1200	19.8800
8	14	20.1200	19.8800
9	16	20.1200	19.8800
10	18	20.1200	19.8800
11	20	20.1200	19.8800
12	22	20.1200	19.8800
13	24	20.1200	19.8800
14	26	20.1200	19.8800
15	28	20.1200	19.8800
16	30	20.1200	19.8800
17	32	20.1200	19.8800
18	34	20.1200	19.8800
19	36	20.1200	19.8800
20	38	20.1200	19.8800
21	40	20.1200	19.8800
22	42	20.1200	19.8800
23	44	20.1200	19.8800
24	46	20.1200	19.8800

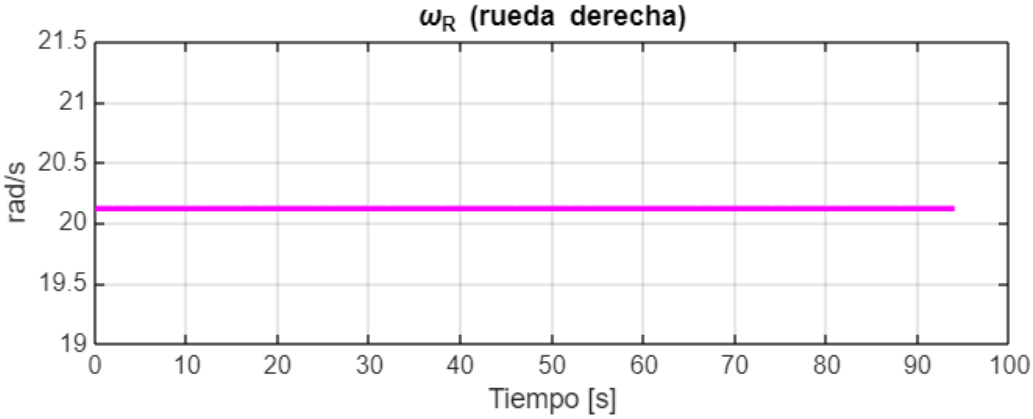
	Tiempo_s	w_R_rad_s	w_L_rad_s
25	48	20.1200	19.8800
26	50	20.1200	19.8800
27	52	20.1200	19.8800
28	54	20.1200	19.8800
29	56	20.1200	19.8800
30	58	20.1200	19.8800
31	60	20.1200	19.8800
32	62	20.1200	19.8800
33	64	20.1200	19.8800
34	66	20.1200	19.8800
35	68	20.1200	19.8800
36	70	20.1200	19.8800
37	72	20.1200	19.8800
38	74	20.1200	19.8800
39	76	20.1200	19.8800
40	78	20.1200	19.8800
41	80	20.1200	19.8800
42	82	20.1200	19.8800
43	84	20.1200	19.8800
44	86	20.1200	19.8800
45	88	20.1200	19.8800
46	90	20.1200	19.8800
47	92	20.1200	19.8800
48	94	20.1200	19.8800

b) Trayectoria



c) Gráfica de las velocidades de las ruedas


ωL (rueda izquierda)
21
20.5
20
19.5
19
18.5
rad/s
0
10
20
30
40
50
60
70
80
90
100
Tiempo [s]


ωR (rueda derecha)
21.5
21
20.5
20
19.5
19
rad/s
0
10
20
30
40
50
60
70
80
90
100
Tiempo [s]