Leader-Follower Trajectory

Coordinate x [m]

Coordinate y [m]

Leader Robot
Follower Robot

Coordinates evolution

p_x/p_y [m]

Time [s]

$p_{L,x}$
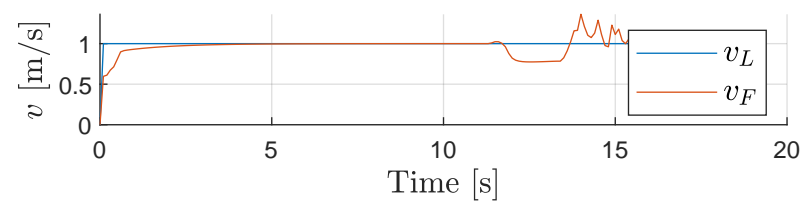$p_{L,y}$
$p_{F,x}$
$p_{F,y}$

Formation error

$error$ [m]

Time [s]
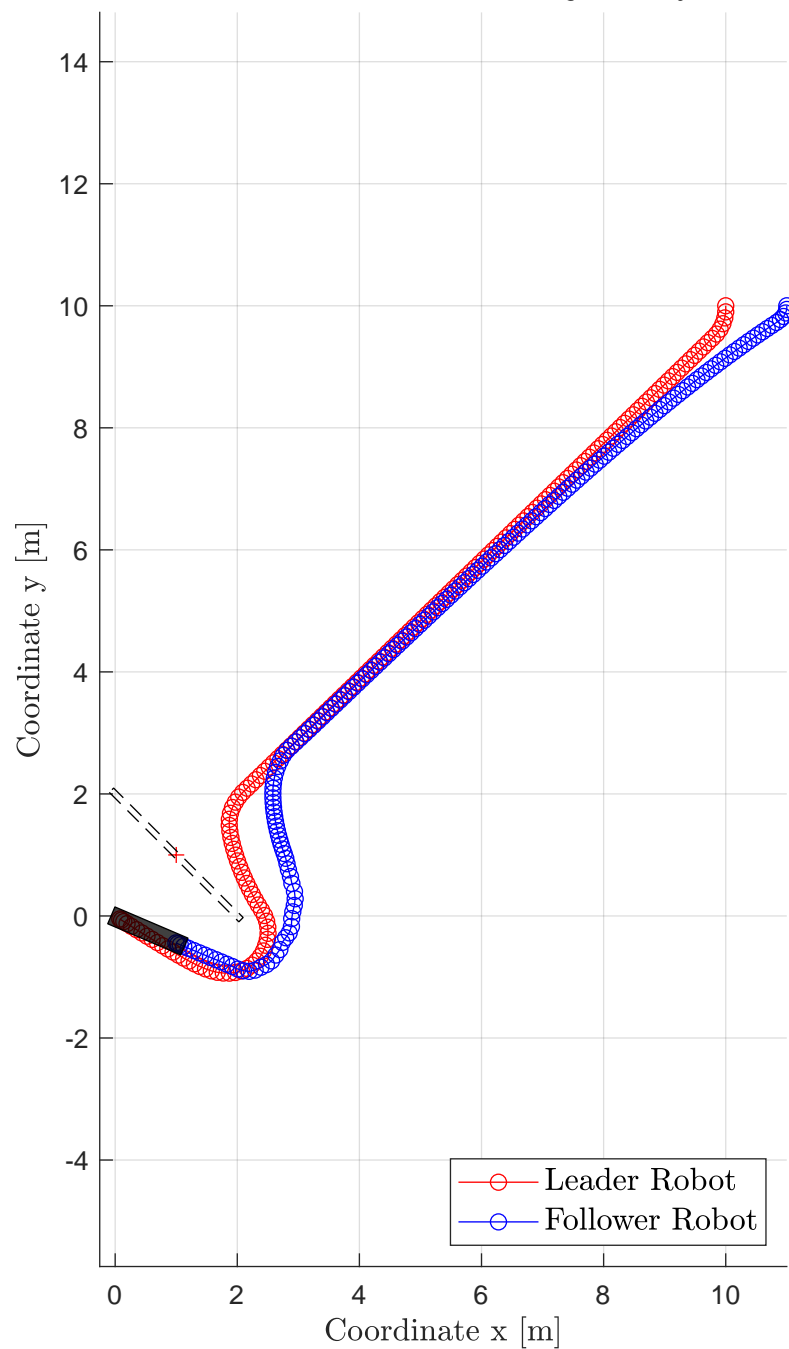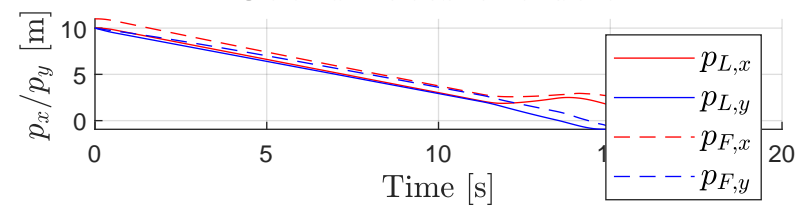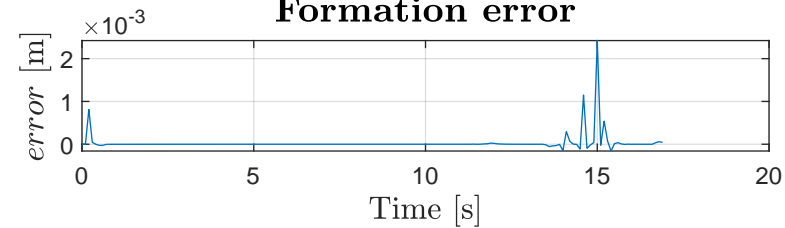
Linear velocities evolution

v [m/s]

Time [s]

v_L
v_F

Angular velocities evolution

ω [rad/s]

Time [s]

ω_L
ω_F