Robot used: turtlebot\_3\_17

Note: the robot slightly turn, when the it is told to go straight (linear velocity 0.2, 5s)

Use the encoder tick to determine the transfer functions

For the angular speed, use the principle of differential drive kinematics

<https://www.cs.columbia.edu/~allen/F17/NOTES/icckinematics.pdf>

Comments about the .csv files present in the folder:

6 tests were run in total. 3 times for the linear velocity and three times for the angular velocity.  
For each type of velocity, a test is run ‘in the air’, meaning the robot is held in my hands, whilst recording a wide range of data. The robot is run on the floor/ground, again recording that wide range of data. And finally it is run on the floor but recording only essential data (to possibly speed up the code).