

```

456 // Controller update loop
457 double UpdateControl() {
...
489 epv = v_ref_x_ - linearSpeedXMps_;
490 epw = w_ref - angularSpeedRads_;
...
542 double W ← summit_xl_trackwidth_;
543 double y1 ← W/2.0;
544 double wx1 ← v_ref_x_ - w_ref_ * y1;
...
546 double q ← -sqrt( wx1*wx1 + wy1*wy1 );
...
576 frw_vel_msg.data = joint_state_.velocity[frw_vel_] q;
...

```

meter-per-second

radian-per-second

meter

meter-per-second

**radian-per-second - meter-per-second**

*Addition of inconsistent units.*