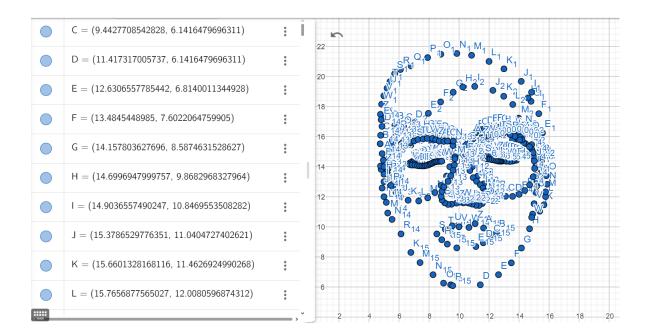
Evaluación 11.2 (Planeación de Trayectorias)



Para desarrolar esta trayectoria use geogebra para generar los puntos de mi rostro como coordenadas y poder hacer el recorrido con el codigo de **PurePursuit (way-points)**, opte por este codigo ya que proporciona un equilibrio ideal entre simplicidad y funcionalidad, permitiendo un seguimiento de trayectorias preciso, adaptable y eficiente, como no realiza mucho procesamiento fue ideal para la enorme cantidad de puntos generados para mi rostro, de igual manera es rapido y facil de modificar sus variables como las velocidades.

```
%% EXAMPLE: Differential drive vehicle following waypoints using the
% Pure Pursuit algorithm
% Copyright 2018-2019 The MathWorks, Inc.
%% Define Vehicle
R = 0.1;
                     % Wheel radius [m]
L = 0.5;
                     % Wheelbase [m]
dd = DifferentialDrive(R,L);
%% Simulation parameters
sampleTime = 0.05;
                             % Sample time [s]
tVec = 0:sampleTime:175;
                             % Time array
initPose = [9.4427708542828;6.1416479696311;0];
                                                      % Initial pose (x y
theta)
pose(:,1) = initPose;
```

```
% Define waypoints
waypoints = [9.4427708542828,6.1416479696311;
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 1; %0
% Create visualizer
viz = Visualizer2D;
viz.hasWaypoints = true;
%% Pure Pursuit Controller
controller = controllerPurePursuit;
controller.Waypoints = waypoints;
controller.LookaheadDistance = 0.2;
controller.DesiredLinearVelocity = 1;
controller.MaxAngularVelocity = 12;
%% Simulation loop
close all
r = rateControl(1/sampleTime);
for idx = 2:numel(tVec)
    % Run the Pure Pursuit controller and convert output to wheel speeds
    [vRef,wRef] = controller(pose(:,idx-1));
    [wL,wR] = inverseKinematics(dd,vRef,wRef);
    % Compute the velocities
    [v,w] = forwardKinematics(dd,wL,wR);
    velB = [v;0;w]; % Body velocities [vx;vy;w]
```

```
vel = bodyToWorld(velB,pose(:,idx-1));  % Convert from body to world

% Perform forward discrete integration step
pose(:,idx) = pose(:,idx-1) + vel*sampleTime;

% Update visualization
viz(pose(:,idx),waypoints);
waitfor(r);
end
```

Warning: System Object 'Visualizer2D' is inherited from mixin class 'matlab.system.mixin.CustomIcon' that will no longer be supported. Remove 'matlab.system.mixin.CustomIcon' and define corresponding System object methods instead.

