Remote Robot:

Kinematic Model

Motor Model

@20Hz

@20Hz

V(t), **ω(t)**

Human Operator:

Control Inputs

Robot Dynamic Model for Estimation

IC: [X(t-T1),Y(t-T1), θ(t-T1)]=Q0

X’,Y’,θ’

X(t-T1),Y(t-T1), θ(t-T1)

@2Hz

X,Y,θ