P1-PERCEPCION Y CONTROL CON EL SANZ EL SOLITARIO

|  |  |  |  |
| --- | --- | --- | --- |
| V(m/s) | Ω(rad/s) | q\_lineal(m) | q\_angular(r) |
| 0.1 | 0 | **O**:0.1095 - **C**:0.1136 | - |
| 0.3 | 0 | **O**:0.3294 - **C**:0.2754 | - |
| 0.5 | 0 | **O**:0.5459 - **C**:0.5611 | - |
| 0.7 | 0 | **O**:0.7696 - **C**:0.7815 | - |
| 0.9 | 0 | **O**:0.9893 - **C**:1.0572 | - |
| 0 | 0.3 | - | **O**:0.0809 - **C**: |
| 0 | 0.7 | - | **O**:0.11380- **C**:0.19254 |
| 0 | 0.9 | - | **O**: - **C**: |

O:OBSERVACION - C:CALCULADO

CALCULADO: Mediante la diferencia entre el espacio recorrido y el número de observaciones

|  |  |  |  |  |
| --- | --- | --- | --- | --- |
| 0.1m/s~0rad/s | 0.3m/s~0rad/s | 0.5m/s~0rad/s | 0.7m/s~0rad/s | 0.9m/s~0rad/s |
| 0.1195 | 0.3600 | 0.5503 | 0.8385 | 0.9893 |
| 0.1100 | 0.3300 | 0.5999 | 0.7702 | 1.0802 |
| 0.1200 | 0.3301 | 0.5538 | 0.7700 | 0.9903 |
| 0.1100 | 0.3302 | 0.5459 | 0.8402 | 0.9893 |
| 0.1102 | 0.3623 | 0.6910 | 0.7696 | PARED |
| 0.1098 | 0.3876 | 0.5500 | 0.8405 | PARED |
| 0.1203 | 0.3597 | 0.5492 | PARED | PARED |
| 0.1204 | 0.3311 | 0.6004 | PARED | PARED |
| 0.1095 | 0.3294 | 0.4998¿P? | PARED | PARED |
| 0.1098 | 0.3297 | PARED | PARED | PARED |
| 0.1104 | 0.3299 | PARED | PARED | PARED |

|  |  |  |
| --- | --- | --- |
| 0m/s~0.3rad/s | 0m/s~0.7rad/s | 0m/s~0.9rad/s |
| 0.16043 | 0.33435 | 0.32921 |
| 0.16664 | 0.24042 | 0.11822 |
| 0.13930 | 0.11380 |  |
| 0.12896 | -0.04799 |  |
| 0.10296 | 0.18686 |  |
| 0.08090 | 0.29844 |  |

AMIGOBOT

|  |  |  |  |
| --- | --- | --- | --- |
| V(m/s) | Ω(rad/s) | q\_lineal(m) | q\_angular(r) |
| 0.1 | 0 | **O**: (0.139) (0.119) (0.129) | - |
| 0.3 | 0 | **O:** (0.388)(0.388) (0.388) | - |
| 0.5 | 0 | **O**: (0.648) (0.620)  (0.599) | - |
| 0.7 | 0 | **O**: (0.598) (0.605) (0.648) | - |
| 0.9 | 0 | **O**: (0.605) (0.648) (0.599) | - |
| 0 | 0.3 | - | **O**: (0.38397) (0.38397) (0.38397) |
| 0 | 0.7 | - | **O:** (0.90757) (0.90757) (0.90757) |
| 0 | 0.9 | - | **O**: (0.95993) (1.1345) (1.0472) |