

Autonomous Mobile Robots

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1 Locomotion & Kinematics

1.1 Positioning

D 1.1.1 (*Position Vector*) ${}^W\mathbf{t}_B = {}^W\mathbf{t}_W {}^W\mathbf{t}_B$, *Original Frame, End point, Target Frame*

D 1.1.2 (*State vector*) x_R : x, v of rob in W , pos of sensors