

Autonomous Mobile Robots

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1 Locomotion & Kinematics

1.1 Positioning

D 1.1.1 (Position Vector) $\underline{W}^t \underline{B}$ = $\underline{W}^t \underline{V} \underline{B}$, Original Frame, End point, Target Frame

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