TA Manual for the Controls Lab

BY Justin Pearson

Humble graduate student January 2017

FIG.5 Diff_x Ofst_x (Diff_y) (Ofst_y) Ps_x Vb_x (Ps_y) (Vb_y) $r_x \cdot \theta b_x$ Ga_x $(r_y \cdot \theta b_y)$ (Ga_y) `*θ* b_x (*θ* b_y) h_x 62_x (62_y) (h_y) 61_x (61_y) Ζ Vw1_x (Vw1_y) F_x (F_y)

Figure 1: Inverted pendulum type vehicle. United States Patent 8,744,688