

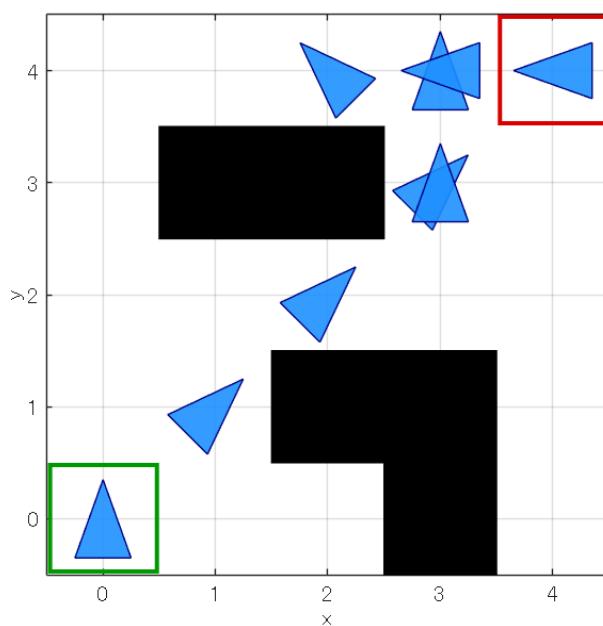
## 移動ロボット制御特論 課題レポート 2

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作成日 2025年 11月 12日

```
%----- 119-138行を修正 -----%
switch theta
    case 0
        dirs = [ 1 -1 -1;  1  0  0;  1  1  1;-1  1 -1; -1  0  0; -1 -1  1];
    case 1
        dirs = [ 1  0 -1;  1  1  0;  0  1  1;-1  0 -1; -1 -1  0;  0 -1  1];
    case 2
        dirs = [ 1  1 -1;  0  1  0; -1  1  1;-1 -1 -1;  0 -1  0;  1 -1  1];
    case 3
        dirs = [ 0  1 -1; -1  1  0; -1  0  1;0 -1 -1;  1 -1  0;  1  0  1];
    case 4
        dirs = [-1  1 -1; -1  0  0; -1 -1  1;1 -1 -1;  1  0  0;  1  1  1];
    case -3
        dirs = [-1  0 -1; -1 -1  0;  0 -1  1;1  0 -1;  1  1  0;  0  1  1];
    case -2
        dirs = [-1 -1 -1;  0 -1  0;  1 -1  1;1  1 -1;  0  1  0; -1  1  1];
    case -1
        dirs = [ 0 -1 -1;  1 -1  0;  1  0  1;0  1 -1; -1  1  0; -1  0  1];
end
%----- 119-138行を修正 -----%
```

Figure 6: Figure X



```
%----- 55行を修正 -----%
xr = [ x + r*sin(th) - r*sin(th - dt), ...
        y - r*cos(th) + r*cos(th - dt), ...
        th - dt ];
%----- 55行を修正 -----%
```

Figure 5: Figure X

