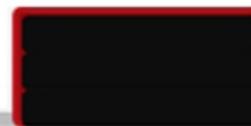
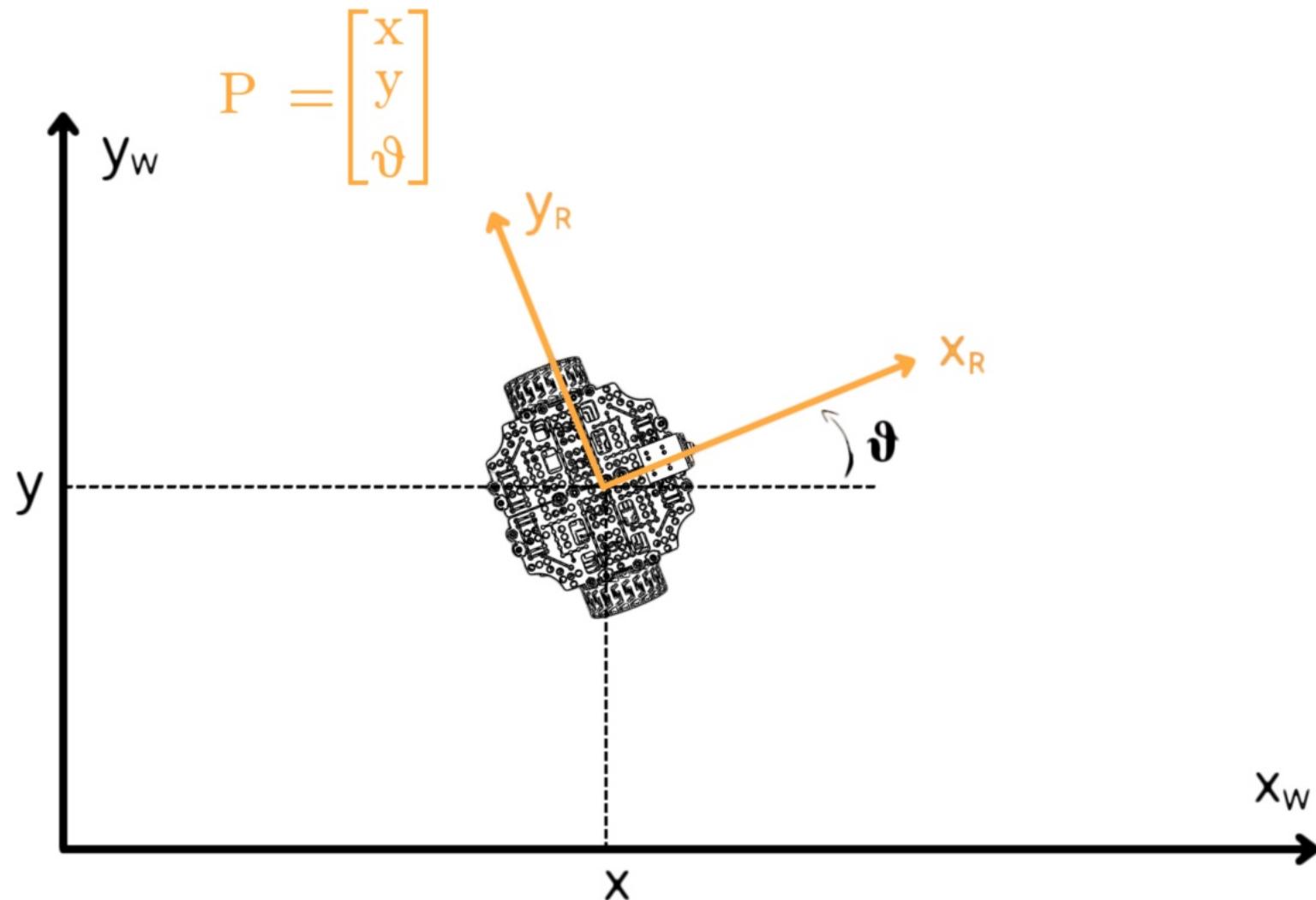
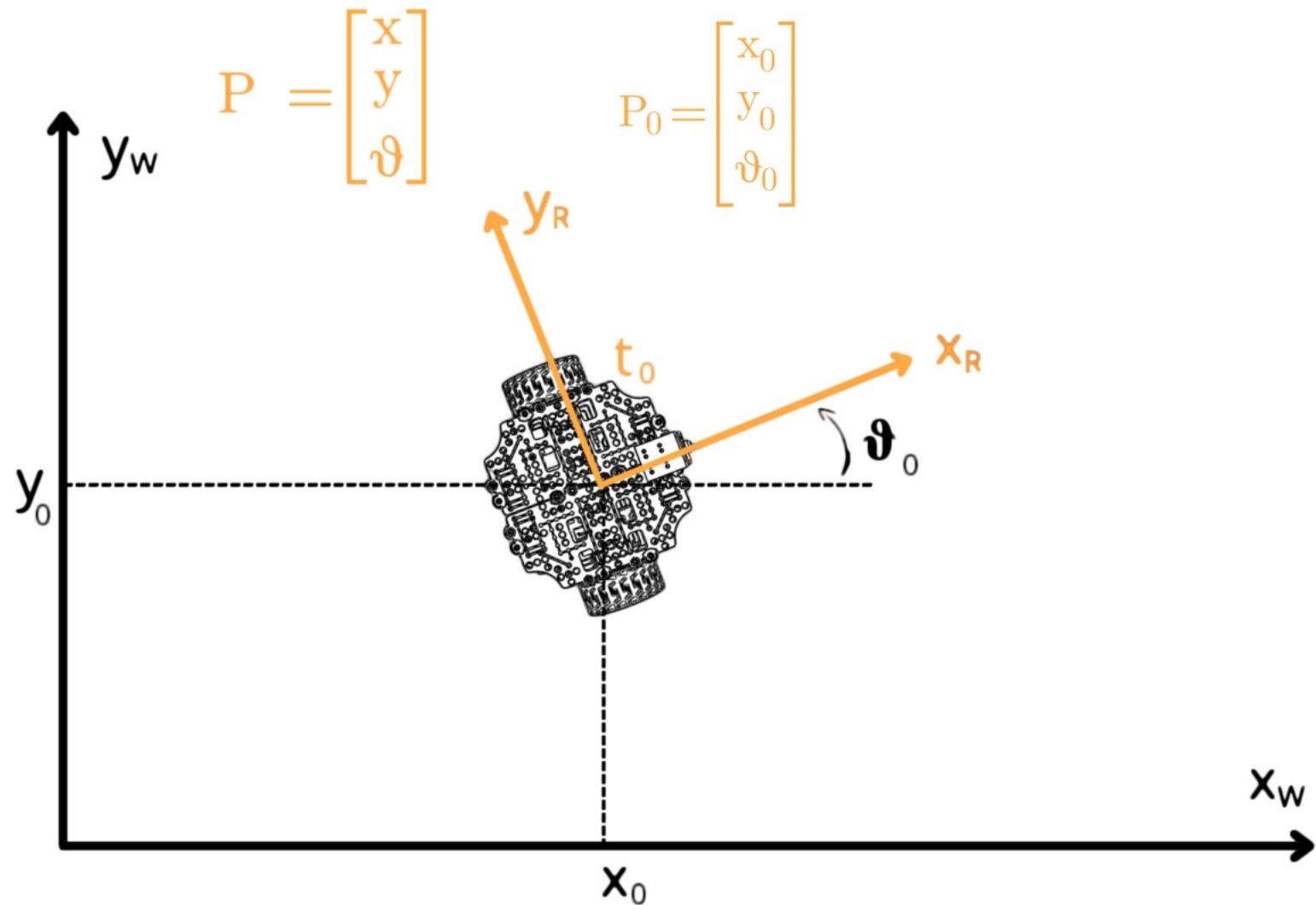
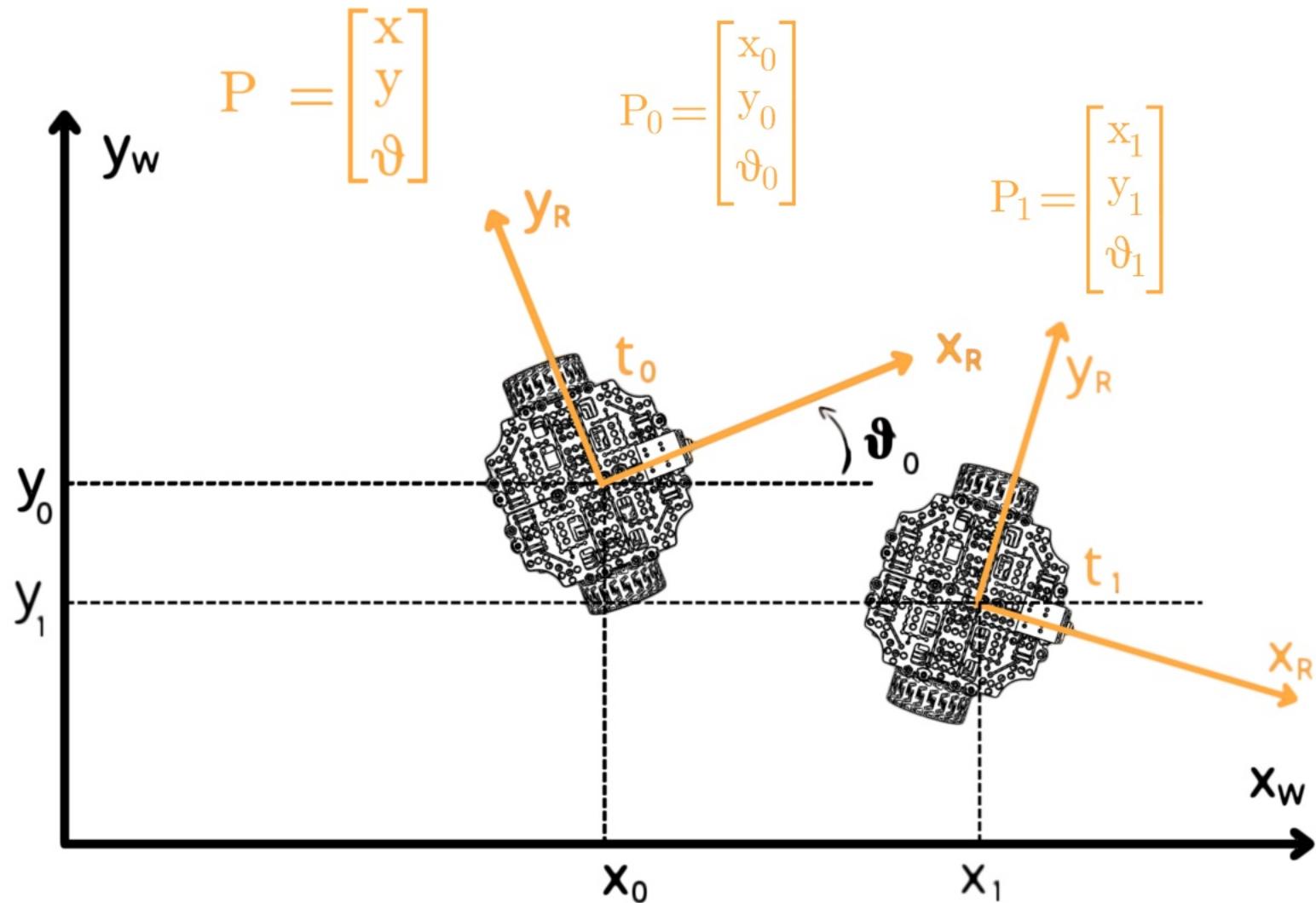
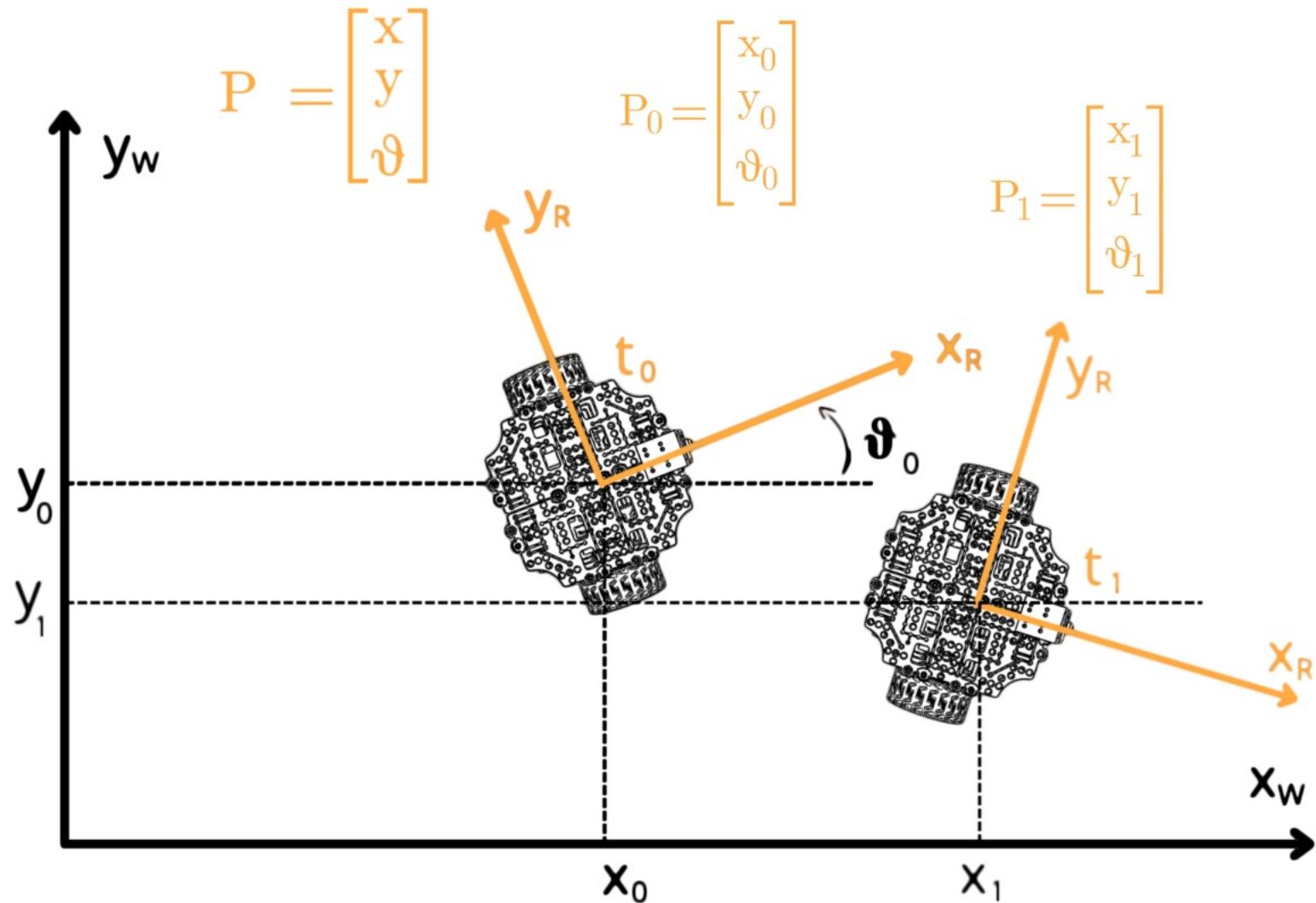


Differential
Kinematics

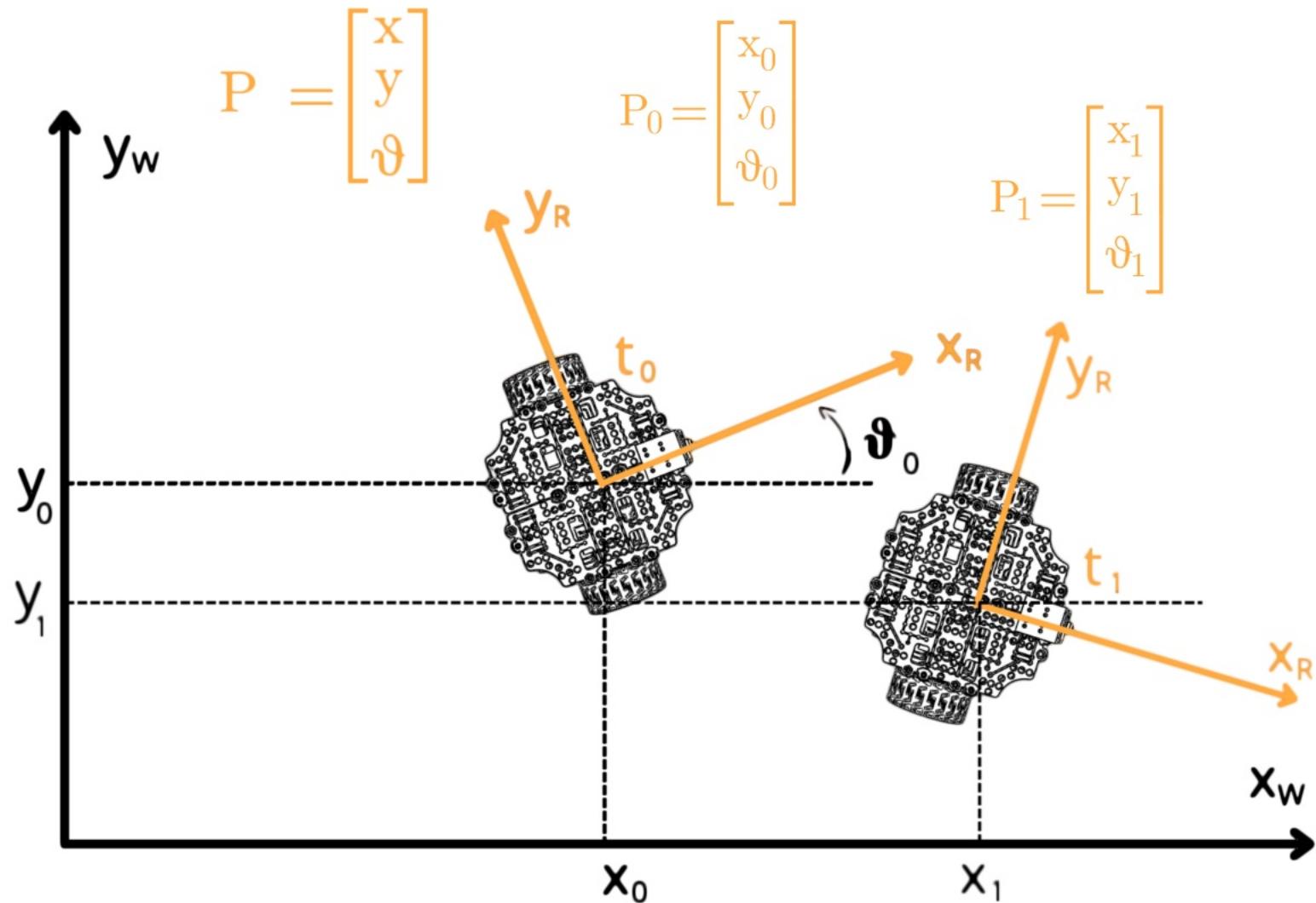


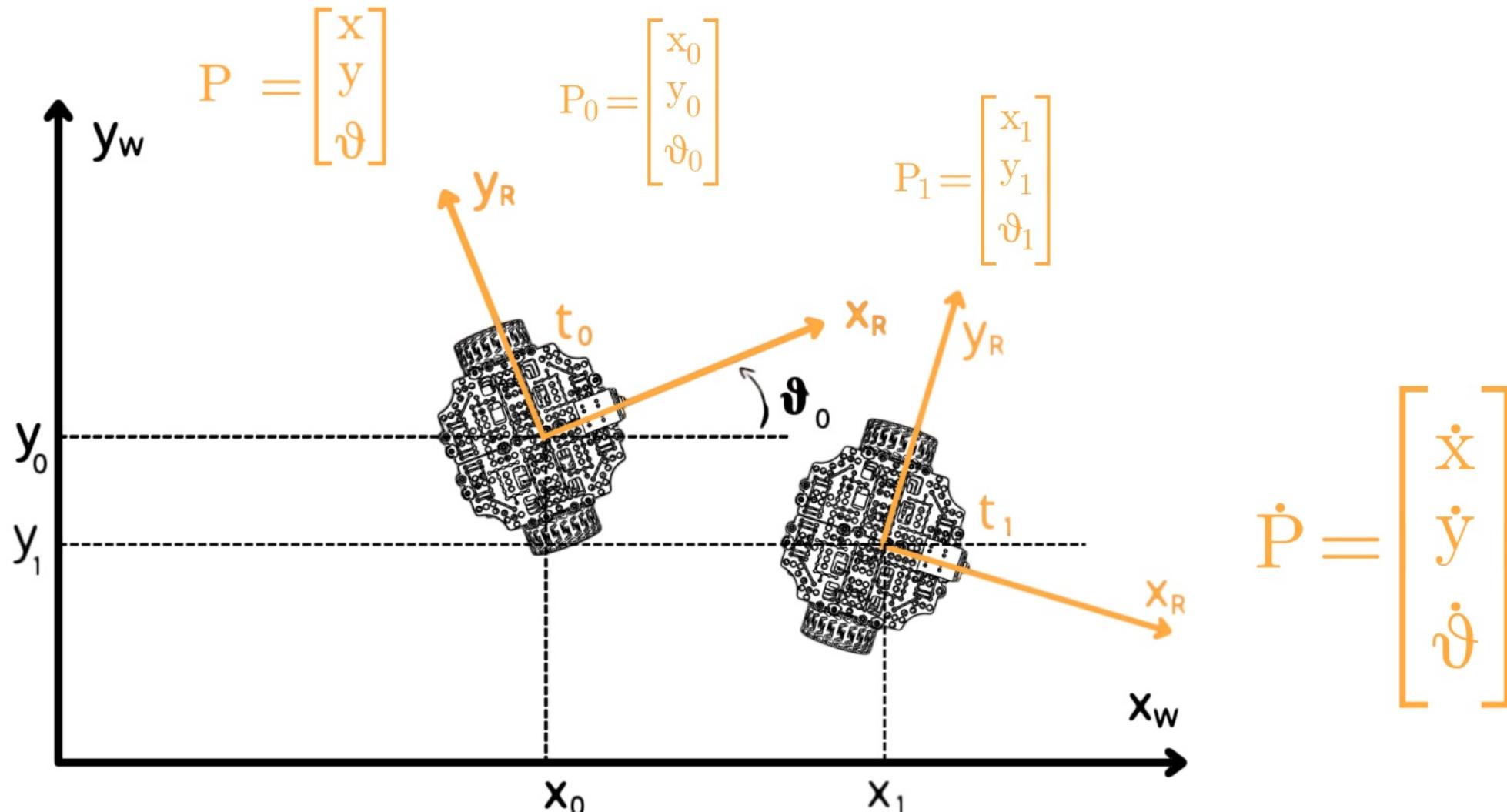




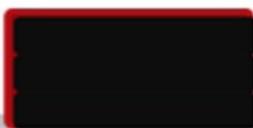
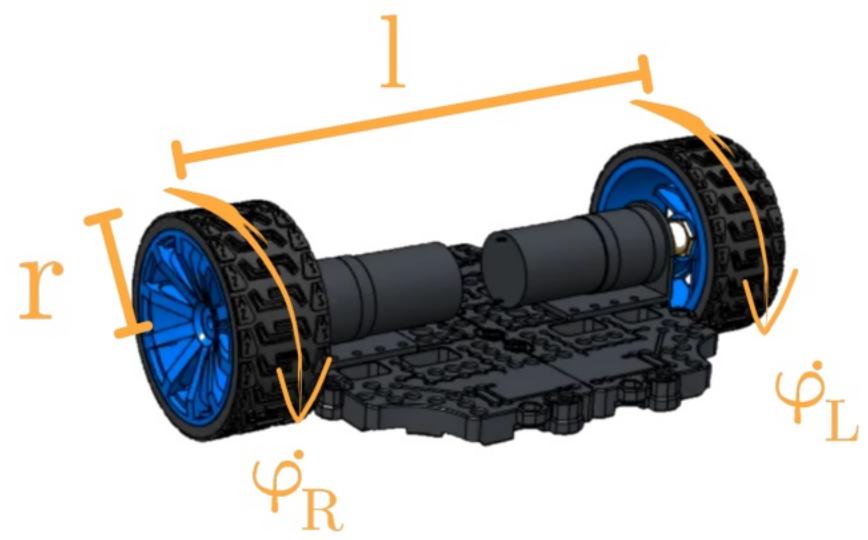


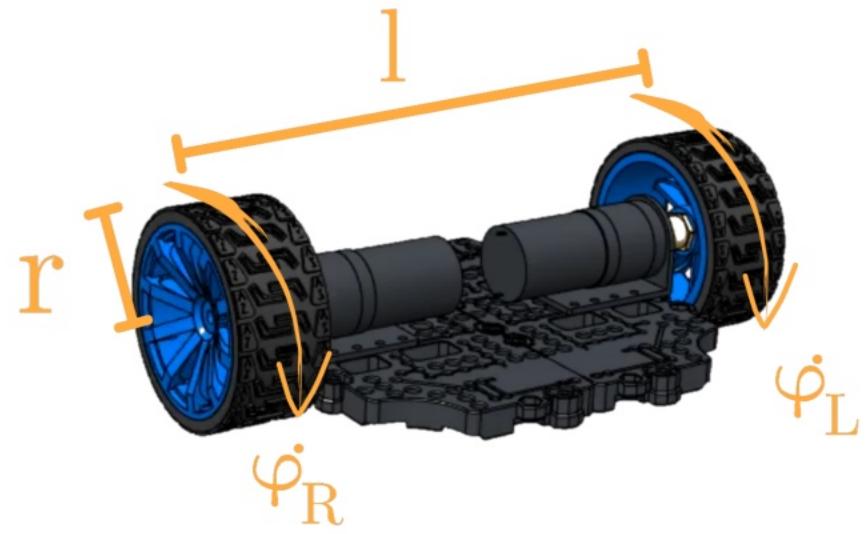
$$\frac{\partial P}{\partial t} = \begin{bmatrix} \frac{\partial x}{\partial t} \\ \frac{\partial y}{\partial t} \\ \frac{\partial \vartheta}{\partial t} \end{bmatrix}$$



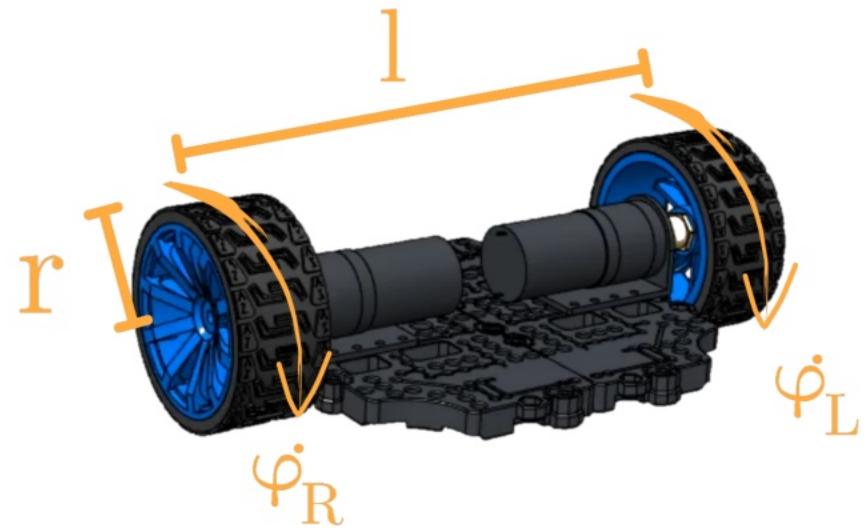


$$\dot{P} = \begin{bmatrix} \dot{x} \\ \dot{y} \\ \dot{\vartheta} \end{bmatrix}$$



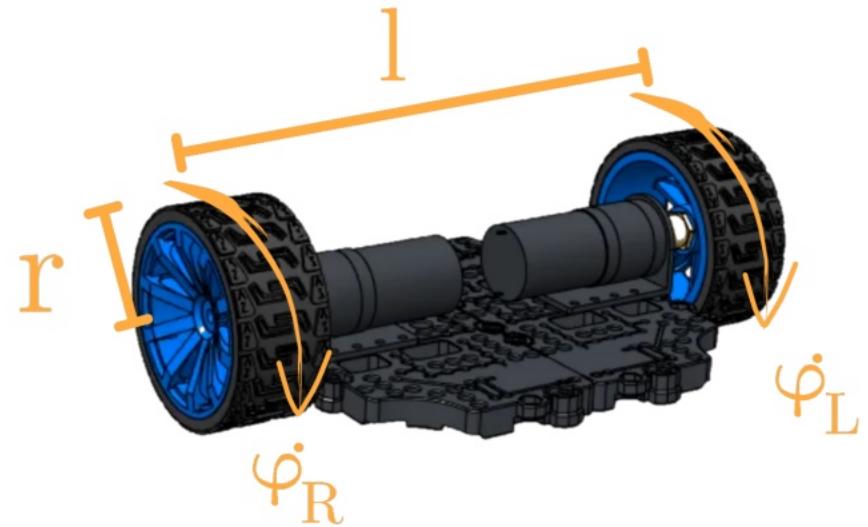


$$\dot{P} = \begin{bmatrix} \dot{x} \\ \dot{y} \\ \dot{\vartheta} \end{bmatrix}$$



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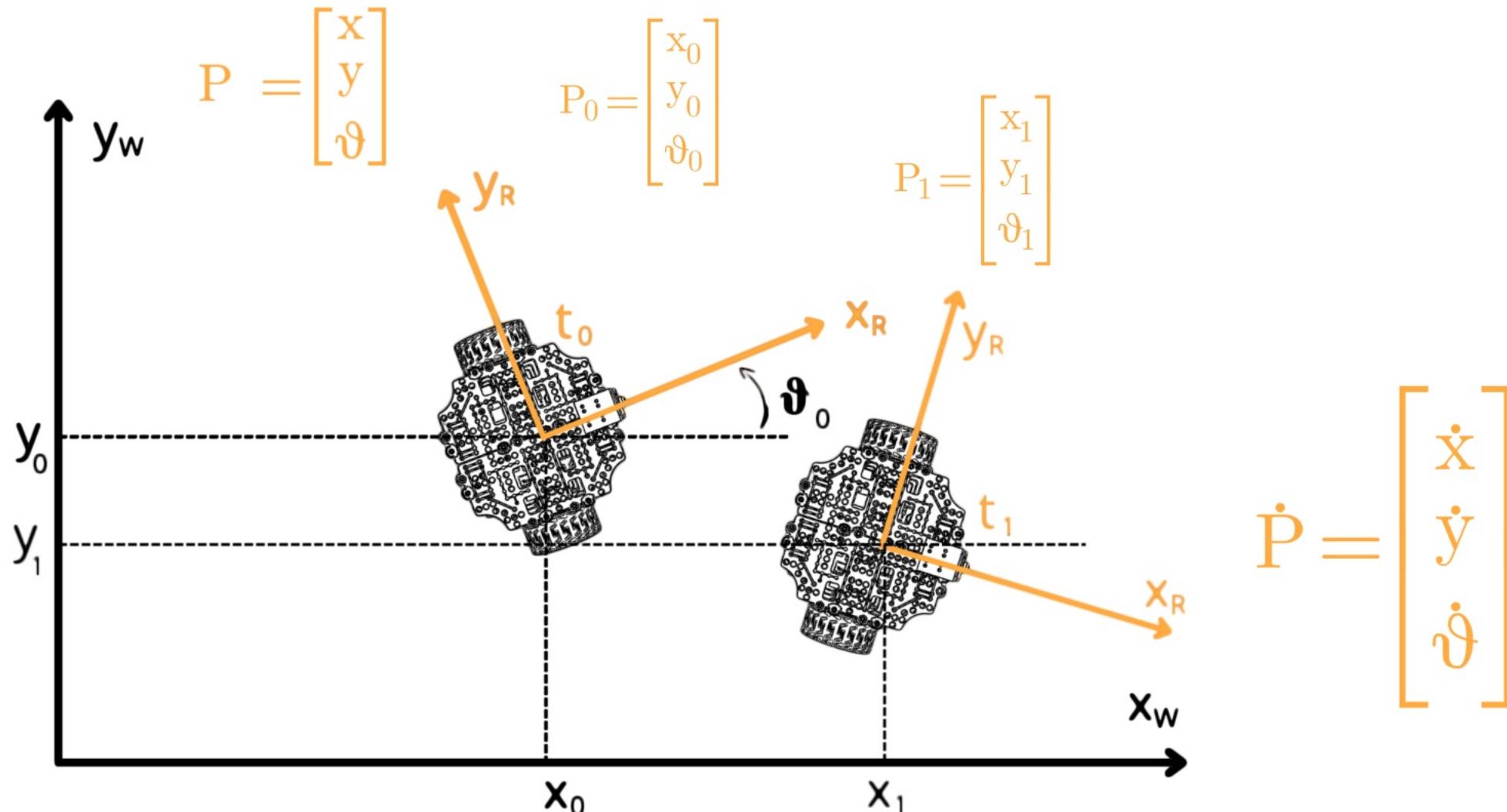
$$\begin{bmatrix} \dot{x} \\ \dot{y} \\ \dot{\vartheta} \end{bmatrix} = f(l, r, \vartheta, \dot{\varphi}_R, \dot{\varphi}_L)$$

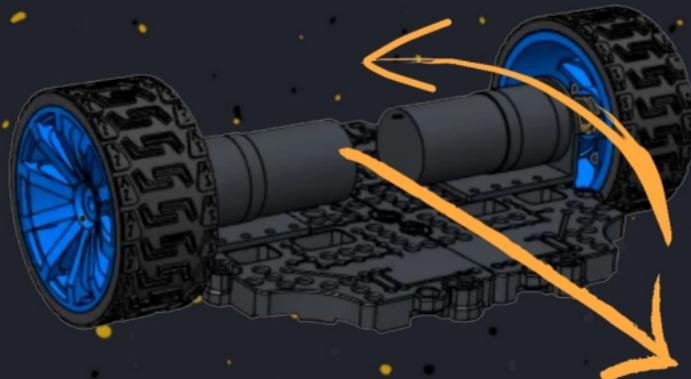
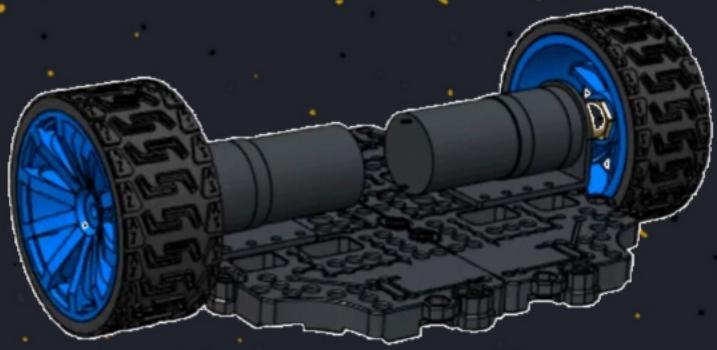


$$\dot{P} = \begin{bmatrix} \dot{x} \\ \dot{y} \\ \dot{\vartheta} \end{bmatrix}$$

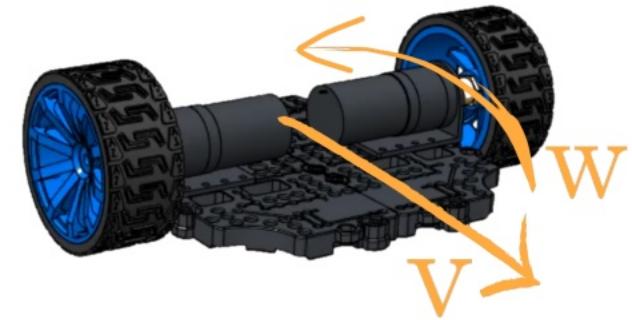
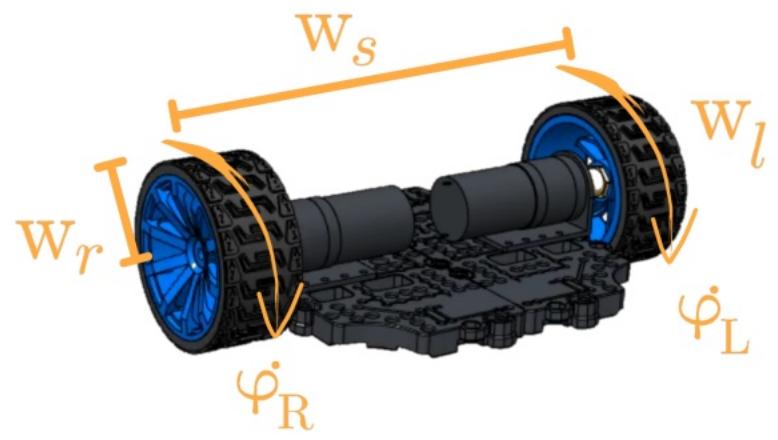
$$\begin{bmatrix} \dot{x} \\ \dot{y} \\ \dot{\vartheta} \end{bmatrix} = f(l, r, \vartheta, \dot{\varphi}_R, \dot{\varphi}_L)$$

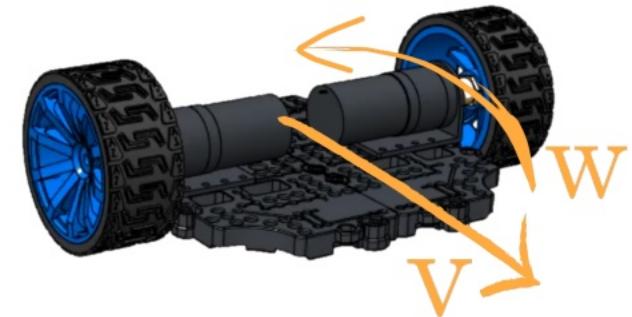
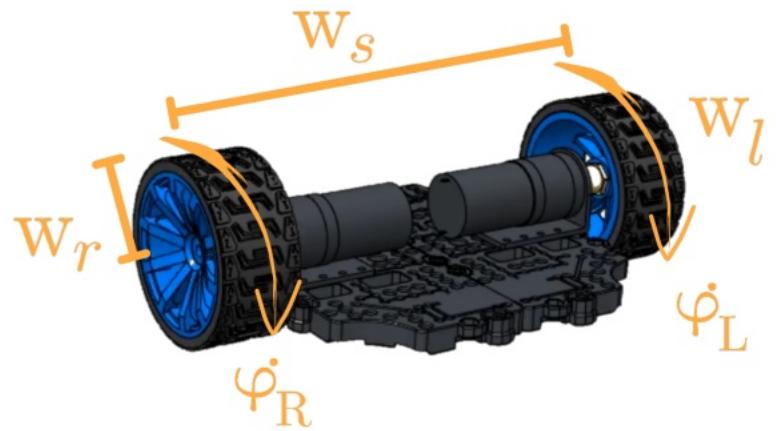
Differential
Kinematics



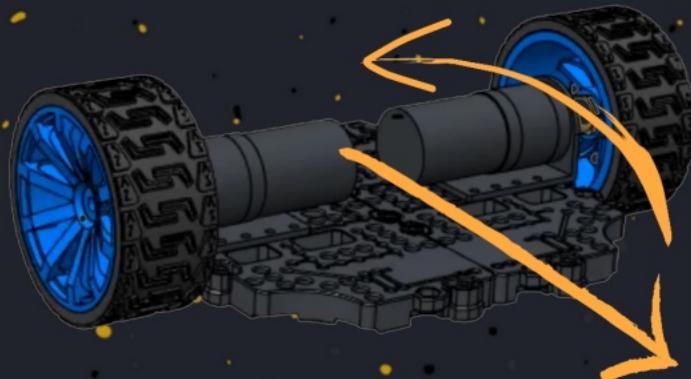
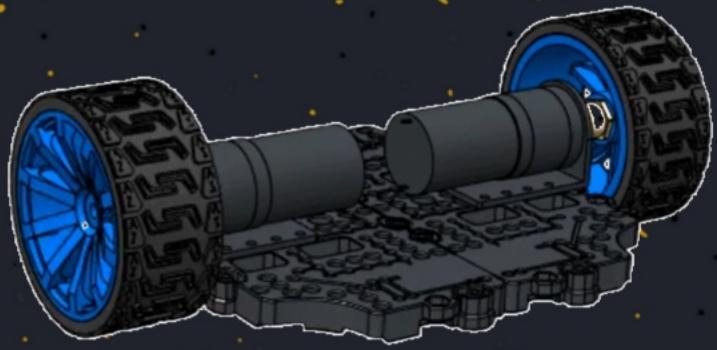


Differential
Kinematics

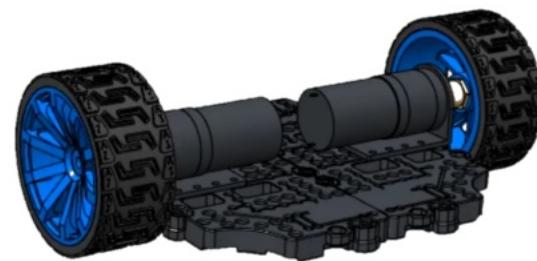
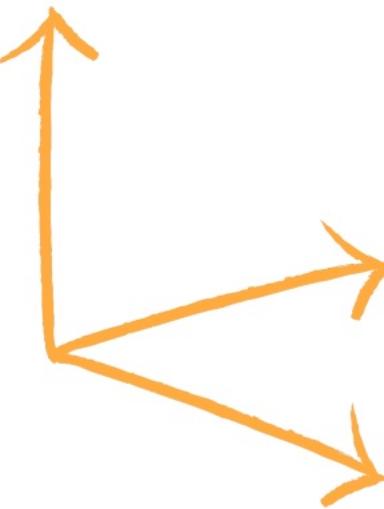
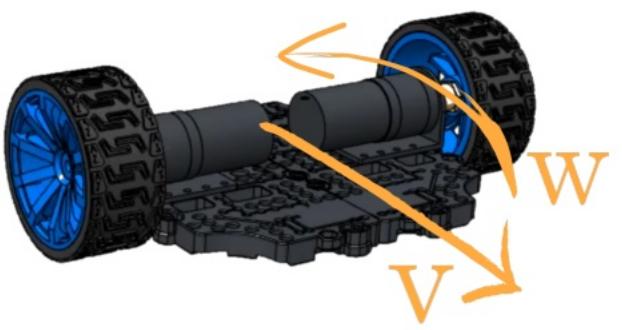


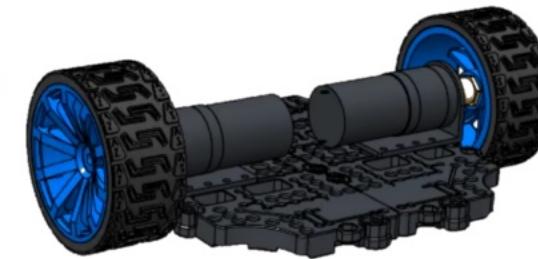
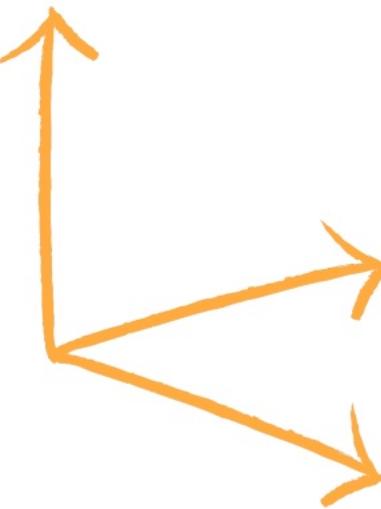
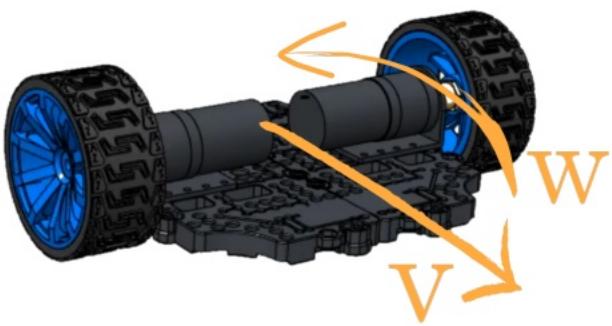


PUT VIDEO ipad
Here (linear and
angular velocity)

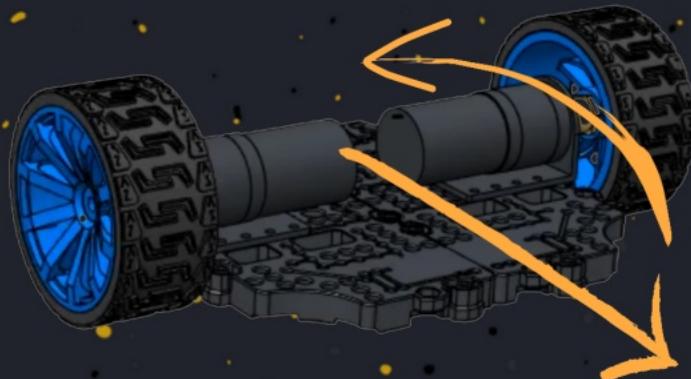
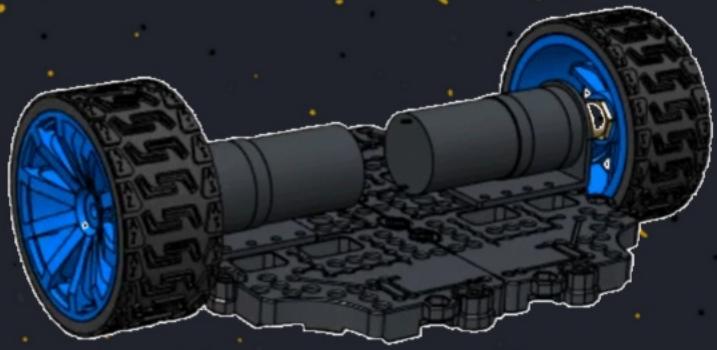


Differential
Kinematics

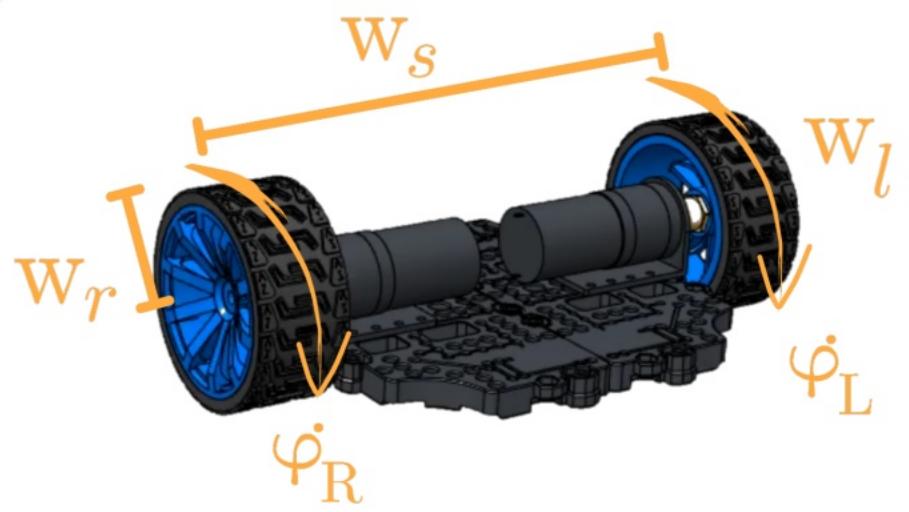


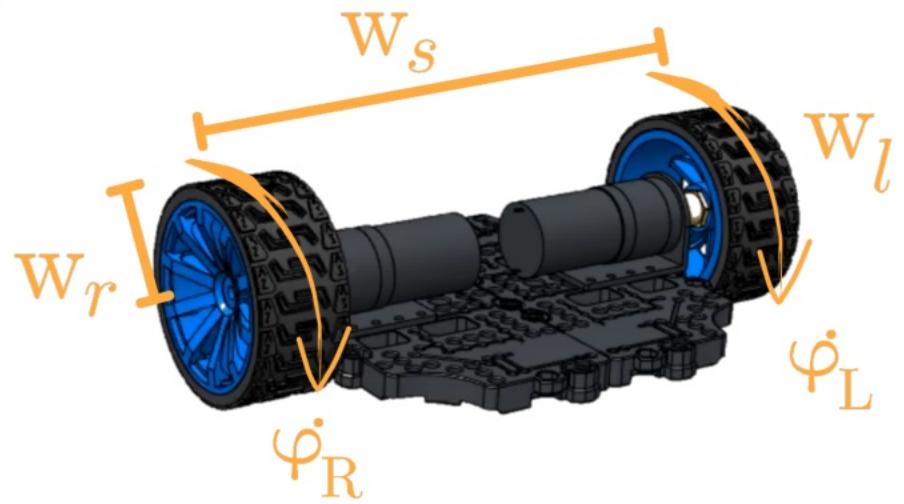


PUT VIDEO ipad
Here (velocity in
world frame)

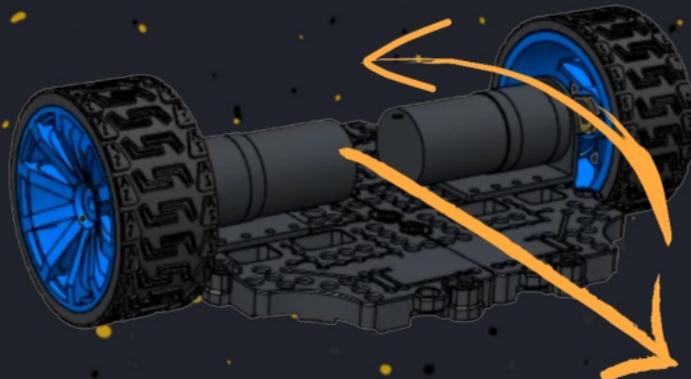
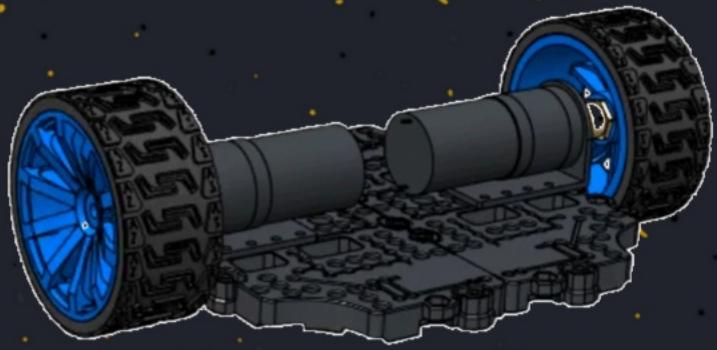


Differential
Kinematics

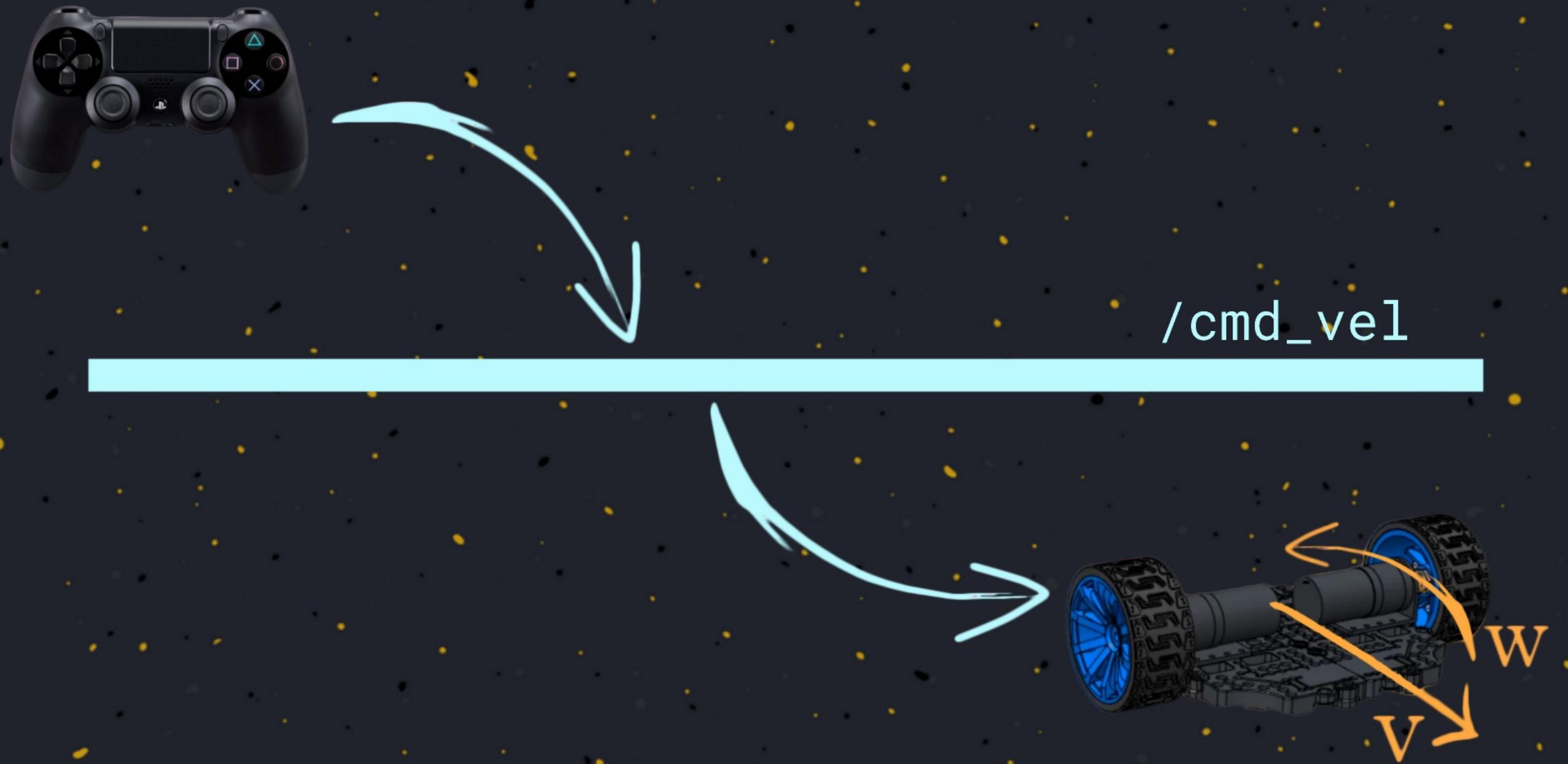




PUT VIDEO ipad
Here (differential
forward
kinematics)



Differential
Kinematics

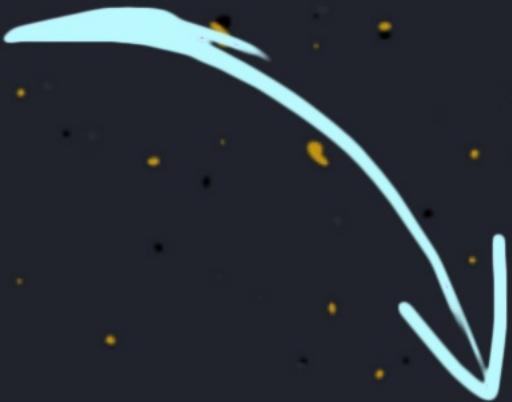




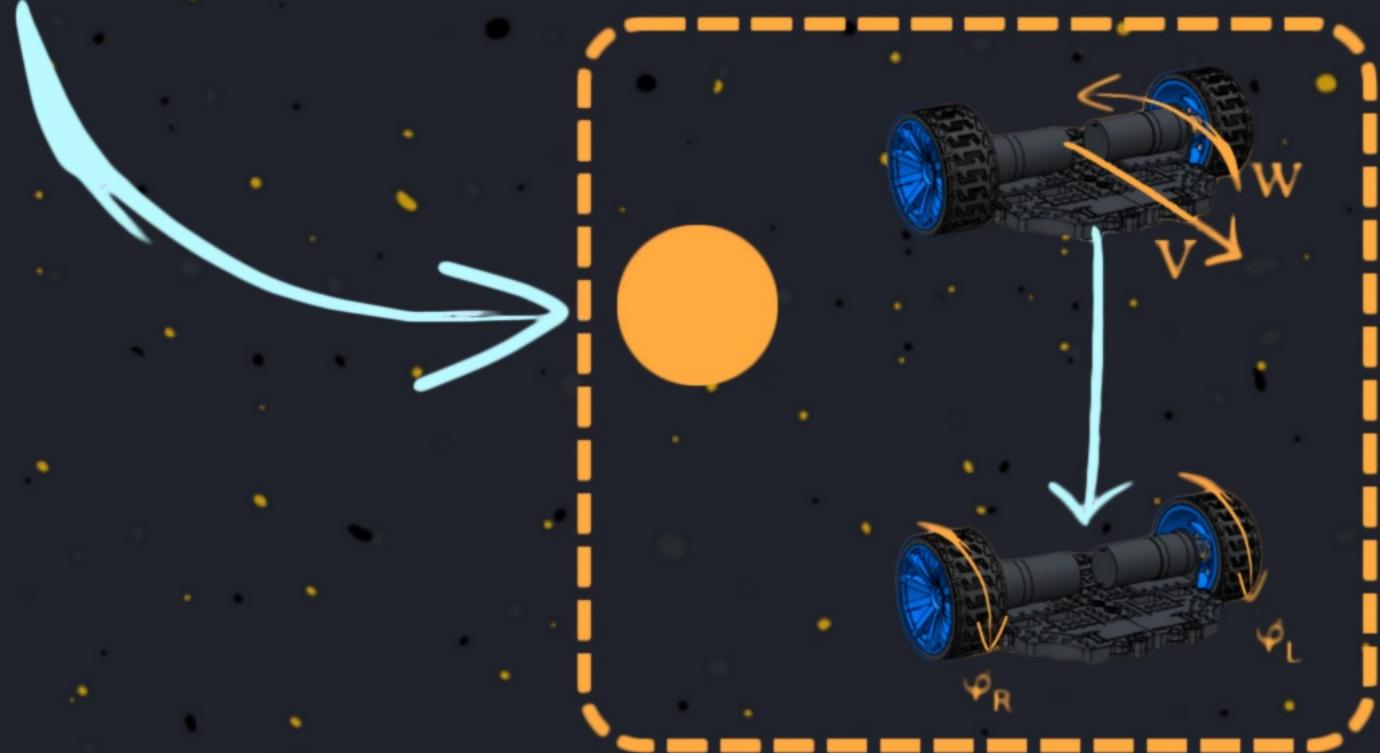


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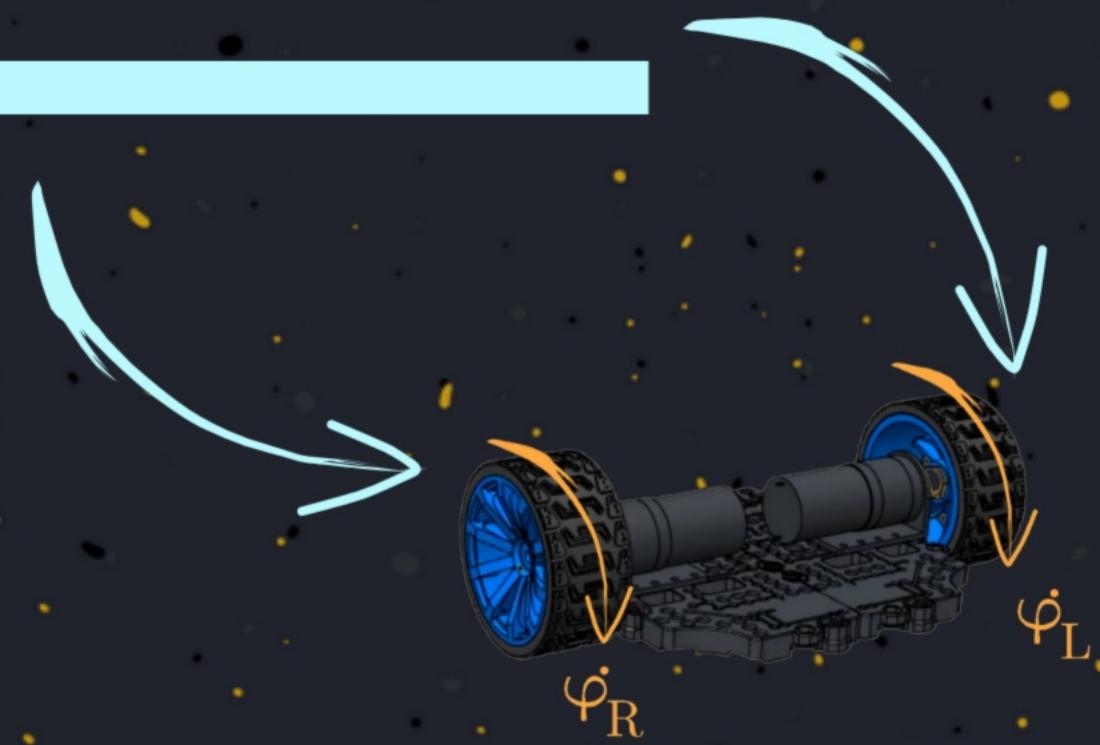
/cmd_vel

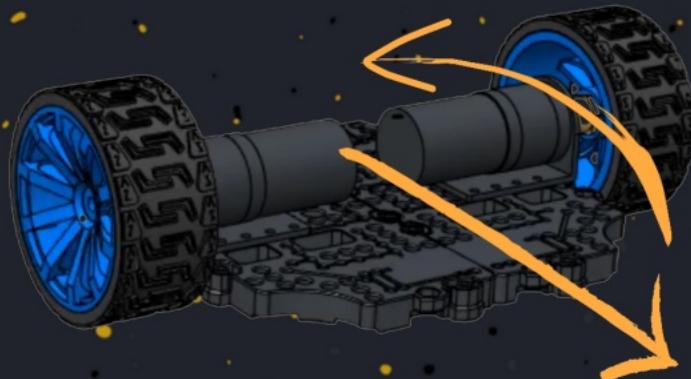
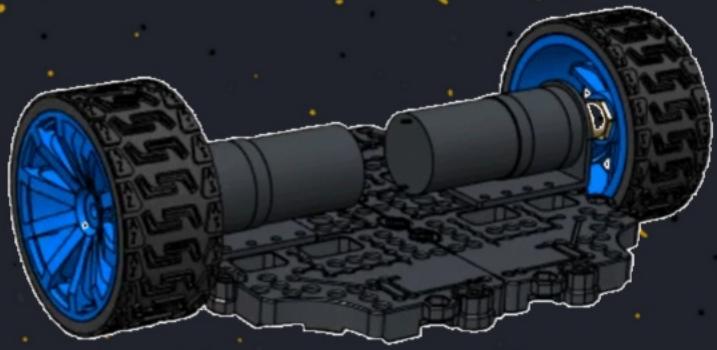




/cmd_vel

/simple_velocity_controller/commands





Differential
Kinematics