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362 | 6

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Articles

Formation tracking for a group of differential-drive mobile robots using an attitude observer

J. González-Sierra , E. Aranda-Bricaire, H. Rodríguez-Cortés & J. Santiaguillo-Salinas

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Abstract

Two trajectory tracking control strategies based on the leader-followers scheme for a group of differential-drive mobile robots are presented where the output to control is the mid-point of the wheels axis of each robot. A third control law is presented to avoid the singularity when the longitudinal velocity of any robot tends to zero. A previously