

Flatness-Based Control: Kinematic Car

Tutorial 5: quasi-static closed-loop controller

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Tasks

1. Implement the quasi-static controller discussed in the notes §4.5.4, p.116–123 in provided class `KinematicCarQuasistaticControl`. This controller uses a moving reference frame with one component tangent to the vehicle path. Use the trajectory generator from Tutorial 4 to provide reference variable values.