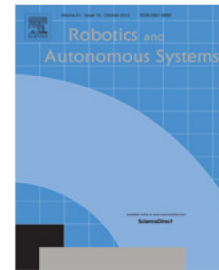


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A comparison of continuous and discrete tracking-error model-based predictive control for mobile robots

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- We present a new continuous tracking-error model-based predictive control algorithm for mobile robots.
- Comparisons are made to our previous work with discrete design.
- Better performance, the design parameters are insensitive to the sampling time.
- Approach enables a non-uniform sampling which is natural in many applications.

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