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Global output-feedback path-following control of unicycle-type mobile robots: A level curve approach

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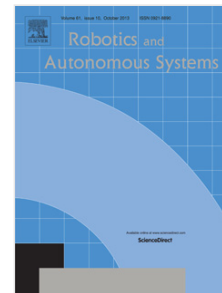
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Level curve approach is used to design path-following controllers for mobile robots.

Interlaced observer is designed to estimate robot velocities and disturbances

The interlaced term is determined during the control design to void difficulties due to observer errors and unbounded reference path derivatives.

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