

## Accepted Manuscript

Sequentially Switched Fuzzy-Model-Based Control for Wheeled Mobile Robot with Visual Odometry

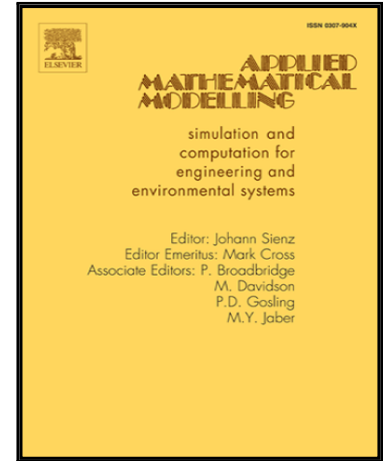
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**Highlight**

- The T-S fuzzy-model-based control for wheeled mobile robot is proposed.
- The visual odometry (VO) is used for robot localization.
- The stabilization is guaranteed based on the Lyapunov stability criterion.
- The practical constraints on the VO is enforced in the control design.

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