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Complete or add frames suitable for the Denavit-Hartenberg (DH) convention for the robot shown in Question 4, and give the table of DH parameters. 7. Consider the differential drive mobile robot (shown below) with wheel spacing, L, left wheel ground velocity, v L, right wheel ground velocity, v R, angular velocity around the ICC, I, and distance between the robot origin and the ICC, R. w ICC R ...

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