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<td>A2.3</td>
<td>Left encoder count after the test run</td>
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<tr>
<td>A2.4</td>
<td>ATMEGA 2560 GUI software</td>
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</table>
LIST OF SYMBOLS, ABBREVIATIONS AND NOMENCLATURE

<table>
<thead>
<tr>
<th>Symbol</th>
<th>Description</th>
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<tbody>
<tr>
<td>ANOVA</td>
<td>Analysis of variance</td>
</tr>
<tr>
<td>CI</td>
<td>Confidence interval</td>
</tr>
<tr>
<td>CVT</td>
<td>Continuously variable transmission</td>
</tr>
<tr>
<td>r</td>
<td>Correlation coefficient</td>
</tr>
<tr>
<td>CCC</td>
<td>Cross coupled control</td>
</tr>
<tr>
<td>DOF</td>
<td>Degree of freedom</td>
</tr>
<tr>
<td>DOE</td>
<td>Design of experiments</td>
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<tr>
<td>DC</td>
<td>Direct current</td>
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<tr>
<td>R</td>
<td>Final orientation of robot</td>
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<tr>
<td>GA</td>
<td>Genetic algorithm</td>
</tr>
<tr>
<td>IR</td>
<td>Infra red</td>
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<tr>
<td>P</td>
<td>Initial orientation of robot</td>
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<tr>
<td>IP</td>
<td>Internet protocols</td>
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<tr>
<td>LED</td>
<td>Light emitting diode</td>
</tr>
<tr>
<td>D_L</td>
<td>Linear distance travelled by left wheel of robot</td>
</tr>
<tr>
<td>D_R</td>
<td>Linear distance travelled by right wheel of robot</td>
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<tr>
<td>LCD</td>
<td>Liquid crystal display</td>
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<tr>
<td>Max</td>
<td>Maximum</td>
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<tr>
<td>Y</td>
<td>Mean</td>
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<tr>
<td>MSS</td>
<td>Mean sum of squares</td>
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<tr>
<td>Min</td>
<td>Minimum</td>
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<tr>
<td>MDOF</td>
<td>Multi degree of freedom</td>
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<tr>
<td>N</td>
<td>Number of experiments</td>
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<td>n</td>
<td>Number of observations</td>
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<td>Abbreviation</td>
<td>Description</td>
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<tr>
<td>$\theta$</td>
<td>Odometry error</td>
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<td>Oe</td>
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<tr>
<td>PC</td>
<td>Percentage contribution</td>
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<td>$V_c$</td>
<td>Pooled error variance</td>
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<tr>
<td>$\mu$</td>
<td>Predicted mean</td>
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<td>PSS</td>
<td>Pure sum of squares</td>
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<tr>
<td>rad</td>
<td>radian</td>
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<tr>
<td>RVC</td>
<td>Regions with velocity constraints</td>
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<tr>
<td>S/N</td>
<td>Signal to noise</td>
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<tr>
<td>SS</td>
<td>Sum of squares</td>
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<tr>
<td>TS</td>
<td>Total sum of squares</td>
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<tr>
<td>USB</td>
<td>Universal serial bus</td>
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<td>VFM</td>
<td>Variable footprint mechanism</td>
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<tr>
<td>W</td>
<td>Wheel base of robot</td>
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<tr>
<td>WMR</td>
<td>Wheeled mobile robot</td>
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<tr>
<td>WLAN</td>
<td>Wireless local area network</td>
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</table>