Paper Title\*

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**Abstract**

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**Keywords:** PID Control, Yaw Correction, Trajectory Planning

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# 1 Introduction

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**Fig. 1** Main structure

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[[8](#_bookmark33), [9](#_bookmark34)]. There is the following relation Eq.1.

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When is small, , if the ramp arc length s is taken as coordinate, , , the corresponding formula.

where, is the yaw angle of the mobile robot; is the length of the ramp; is the variation of the angle between the ramp and the ground.

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**Table 1.** Table Head

|  |  |  |  |  |  |  |
| --- | --- | --- | --- | --- | --- | --- |
| Table Head | Subhead | Subhead | Subhead |  |  |  |
| **F1** | 1.143 | 0.285 | 0.286 |  |  |  |
| **F2** | 1.143 | 0.285 | 0.067 |  |  |  |
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# DECLARATIONS

## Ethics approval and consent to participate

Not applicable.

## Conflict of interest

No potential conflict of interest was reported by the authors.

## Dataset to be available

All data generated or analyzed during this study are included in this published article.

## Consent for publication

Not applicable.

## Funding

Not applicable

## Acknowledge

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He is mainly engaged in the research of information product design, technology design, human-computer interaction, industrial design, digital art and design.

## Abbreviatiuons

PID proportional-integral-derivative

DC direct current motor

CDU current differential unit

CRU current replication unit

CSU current squarer unit

TAU transconductance amplifier unit

CDBA current differential buffer amplifier

AR augmented reality

ADC voltage double closed-loop

RTK real-time kinematic

# Appendix A Relevant data and information

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