	TRUE	FALSE
1. For a two-wheeled differentially steered robot, for any given wheel speeds, one can always find an instantaneous center of rotation.	☐	☐
2. Odometry can be made completely accurate, by simply reducing the integration time step dt as much as possible.	☐	☐
3. When a torque is applied to a wheel, the forward-pointing (friction-generated) force equals the torque divided by the radius of the wheel.	☐	☐

1. This is true. No matter what the wheel speeds are, there is always a point (which, of course, moves around with the robot, and as the wheel speeds change) such that the robot's motion can be described as a pure rotation around the same point.

2. This is false: Even though one can reduce the odometric error by using a small dt, one cannot eliminate altogether since (for example) the encoder wheels have a limited number of sectors and the kinematic model is also never perfectly accurate.

3. This is false (see the left panel of Fig. 2.3 in the lecture notes): If it were true, the wheel would not rotate (see Eq. (2.13)). Instead, it is the difference between (i) the torque and (ii) the product of the forward-pointing (friction-generated) force and the wheel radius that causes the rotation of the wheel.