

Sensor Ports

px
py
pa
tx
ty
ta

d_{getPos}

p0x
p0y
p0a
t0x
t0y
t0a

t_{Error}

Error = 2

t_{Turn}

Idle = 1

d_{getErr}

turn

$d_{\text{RightMotor}} = 1$

gust

$d_{\text{LeftMotor}} = 1$

rjet

ljet

Actuator
Ports

ex
ey
ea
ea2

=200ms

