PID Navigation for Sanic MARV Group 1 Hail Shrek UwU

is die error, so die . G, KI en KD is set gains vir elke deel van die signal.

Stap een is die error funksie:

|  |  |  |  |  |  |
| --- | --- | --- | --- | --- | --- |
| LL | L | M | R | RR | e(t) |
|  |  | X |  |  | 0 |
|  |  |  |  |  |  |
|  |  |  |  |  |  |
|  |  |  |  |  |  |

Function e(t) vat ’n vector van inputs.