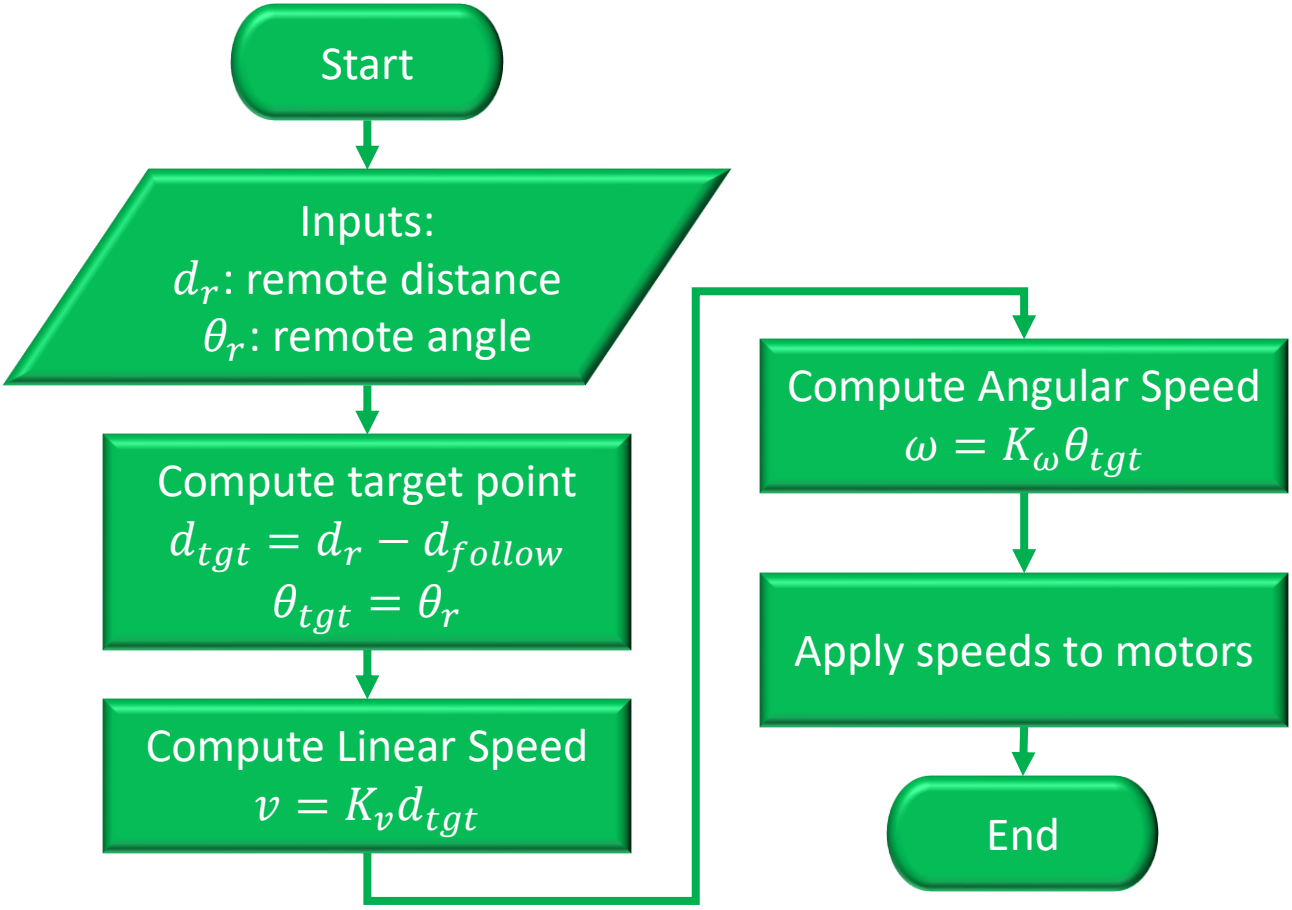
Start
Inputs:
d_r: remote distance
θ_r: remote angle
Compute target point
$d_{tgt} = d_r - d_{follow}$
$\theta_{tgt} = \theta_r$
Compute Linear Speed
$v = K_v d_{tgt}$
Compute Angular Speed
$\omega = K_\omega \theta_{tgt}$
Apply speeds to motors
End