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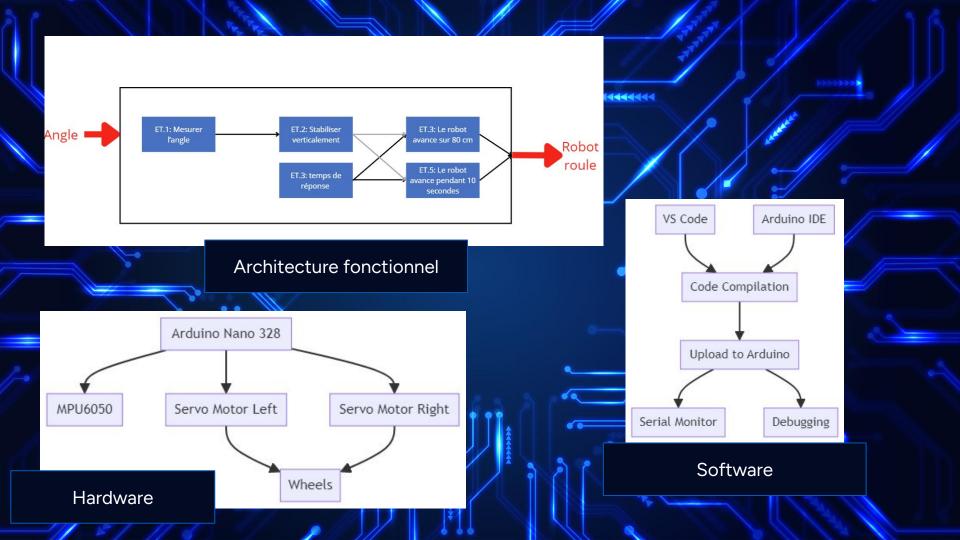
00 01 02

Introduction Mesure angle Maintient à la inclinaison verticale

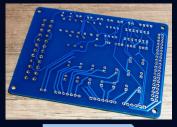
**0**3 **0**4 **0**5

(ET3) Marche avant Marche avant vitesse constante





## Hardware



PCB



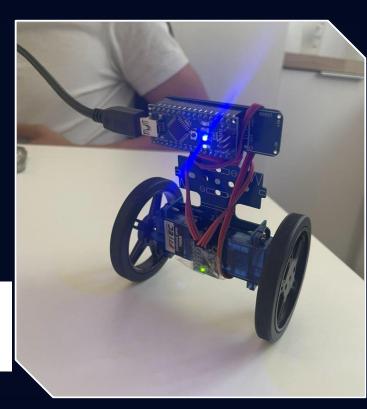
Arduino nano 328



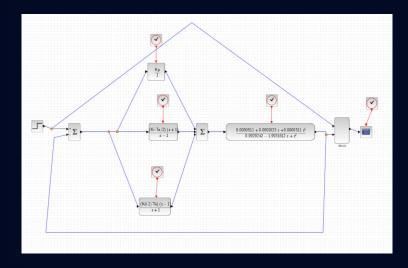
MPU6050

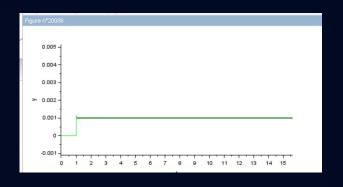


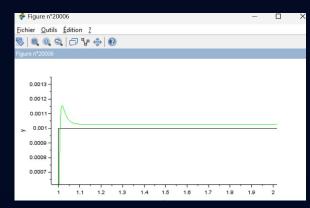
Servos



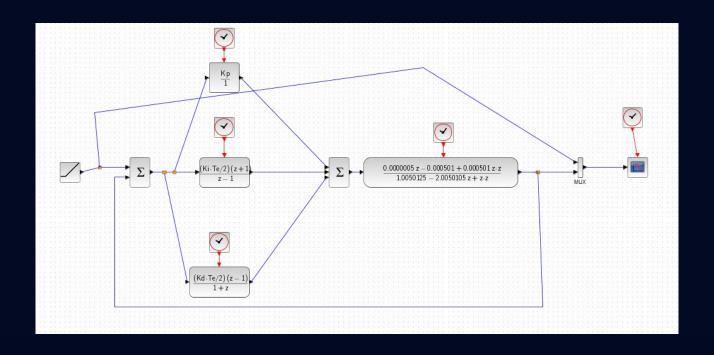
## Simulation en Z (1)



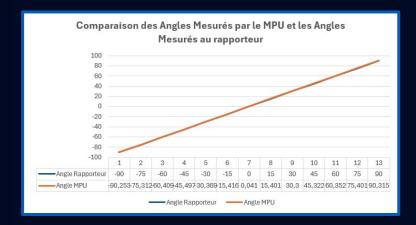




## Simulation en Z



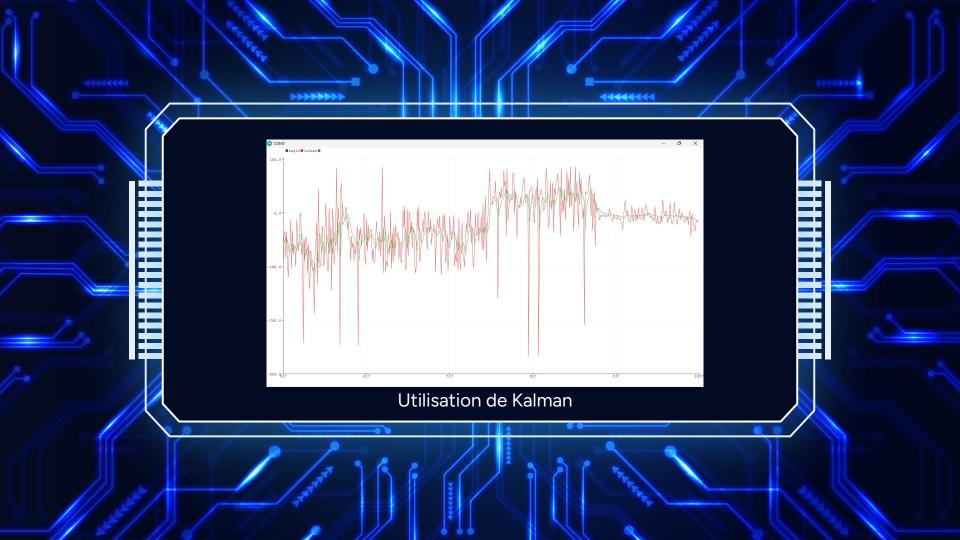
#### ET1. Angle Inclinaison

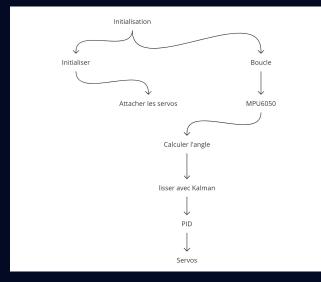












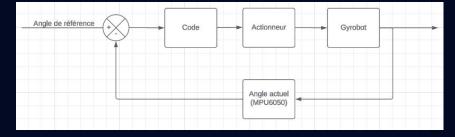
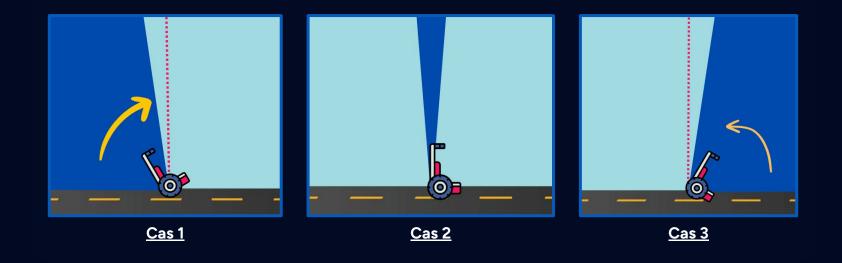


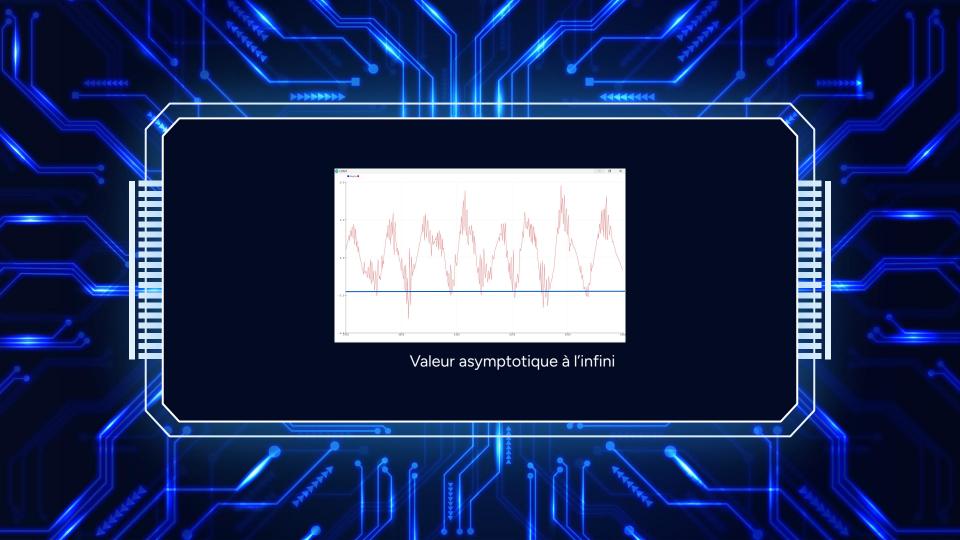
Schéma blok

Organigramme

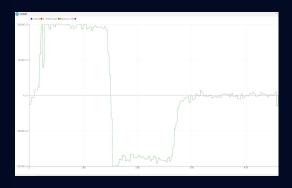
### ET2. Maintient à la verticale











Utilisation PID calibré

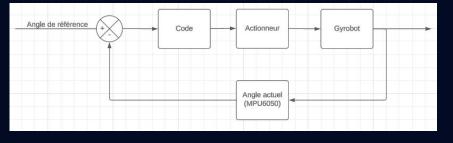
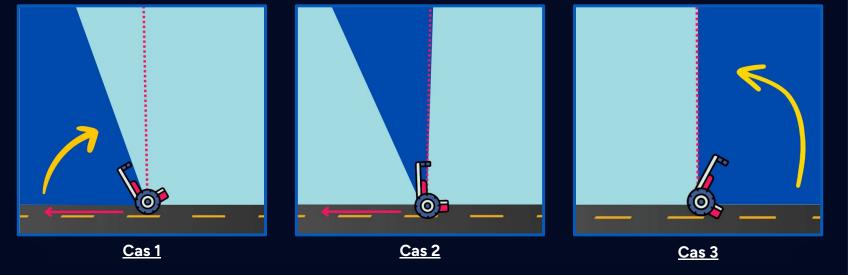


Schéma blok

### ET4. Marche avant





### Conclusion





Gérer tous les examens qui allaient avec.



#### Etape par etape

Reconsiderer notre approche des projets.



#### Communiquer

Garder un esprit d'équipe axer vers le dialogue pour favoriser l'avancée du projet.