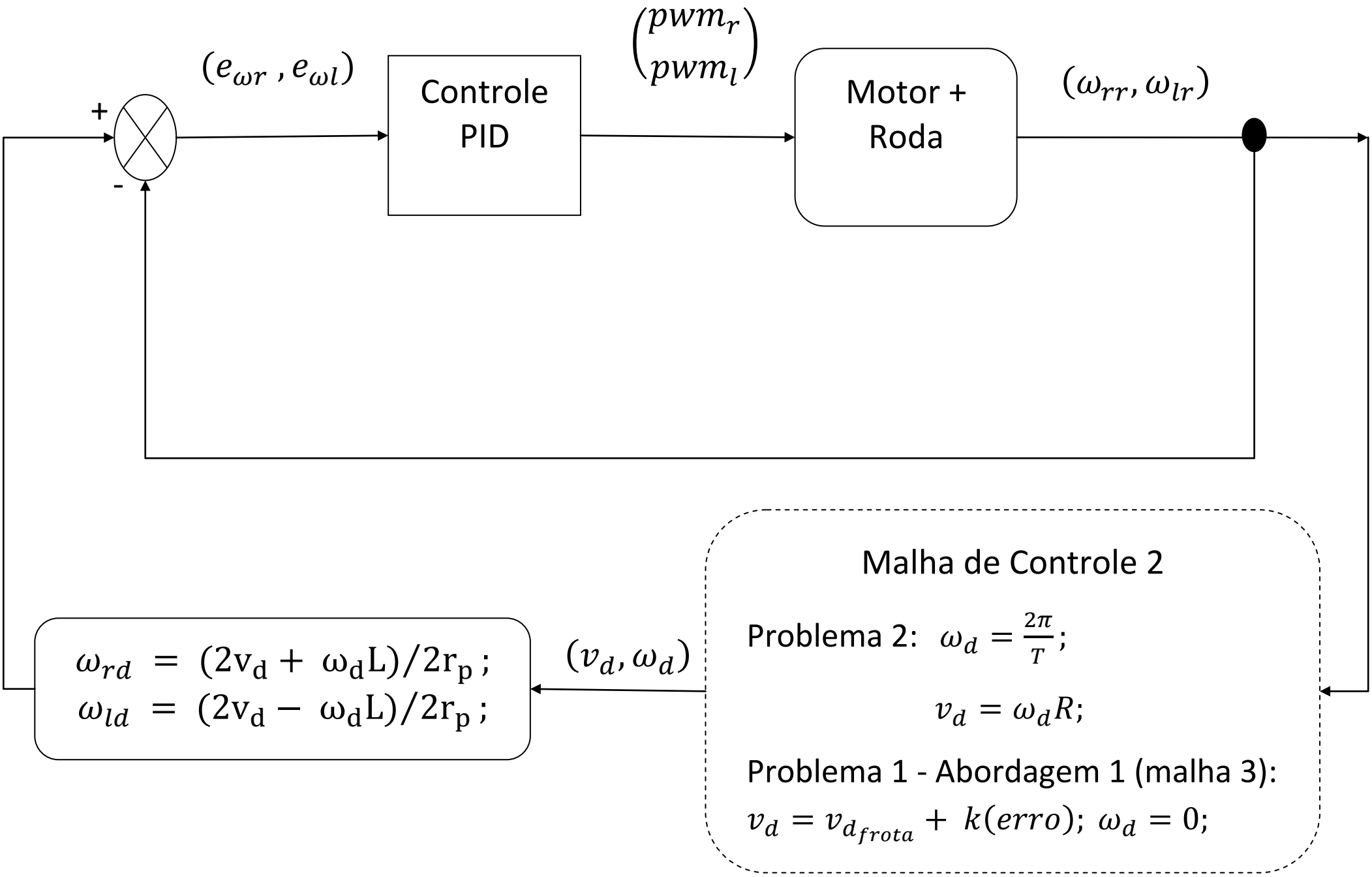
$(e_{\omega r}, e_{\omega l})$
$\begin{pmatrix} pwm_r \\ pwm_l \end{pmatrix}$
$(\omega_{rr}, \omega_{lr})$
+
-
Controle PID
Motor + Roda
$\omega_{rd} = (2v_d + \omega_d L)/2r_p;$
$\omega_{ld} = (2v_d - \omega_d L)/2r_p;$
(v_d, ω_d)
Malha de Controle 2
Problema 2: $\omega_d = \frac{2\pi}{T};$
$v_d = \omega_d R;$
Problema 1 - Abordagem 1 (malha 3):
$v_d = v_{d_{frota}} + k(erro);\ \omega_d = 0;$