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Rumus V2.

** Delta position.

$dX = X_t - X$ Dimana : dX = delta X Y_t = Target Y

$dY = Y_t - Y$ dY = delta Y θ_t = target sudut (radians)

$d\omega = \theta t - \theta$ X_t = Target X θt = sudut sekarang (radians).

** Perhitungan jarak tempuh terdekat.

$S = \int dx^2 + dy^2$

** Hitung kecepatan arah sumbu X dan Y (vektor global.

$Vx = V \times dX/s$ dimana V = Speed/kecepatan.

$Vy = V \times dx/s$

** Transformasi Global ke local.

~~** V1 = (cos(θ) ...~~

$V_{x\_local} = (\cos(\theta) \times Vx) + (\sin(\theta) \times V_Y)$

$V_{Y\_local} = (-\sin(\theta) \times Vx) + (\cos(\theta) \times V_Y)$

** kecepatan sudut motor.

$w1 = (2/3 \times V_{x.local}) + (1/3 \times w)$

$w2 = (-1/3 \times V_{x local}) + (1/\sqrt{3} \times V_{y.local}) + (1/3 \times w)$

$w3 = (-1/3 \times V_{x local}) + (-1/\sqrt{3} \times V_{y.local}) + (1/3 \times w)$

KIKY