





```
wb_motor_set_velocity(left_motor, left_speed);  
wb_motor_set_velocity(right_motor, right_speed);
```

```
rotation_counter_2 = 0;  
role_value = wb_inertial_unit_get_roll_pitch_yaw(inner);
```

方向決定ルーチン
2

rotation_counter_2 == 0

Yes

No

rotation_counter_2 > 0

Yes

```
rotation_counter_2--;  
left_speed = -2;  
right_speed = 2;
```

No

```
rotation_counter_2++;  
left_speed = 2;  
right_speed = -2;
```

```
wb_motor_set_velocity(left_motor, left_speed);  
wb_motor_set_velocity(right_motor, right_speed);
```

```
wb_motor_set_velocity(left_motor, 10);  
wb_motor_set_velocity(right_motor, 10);
```

ゴール







