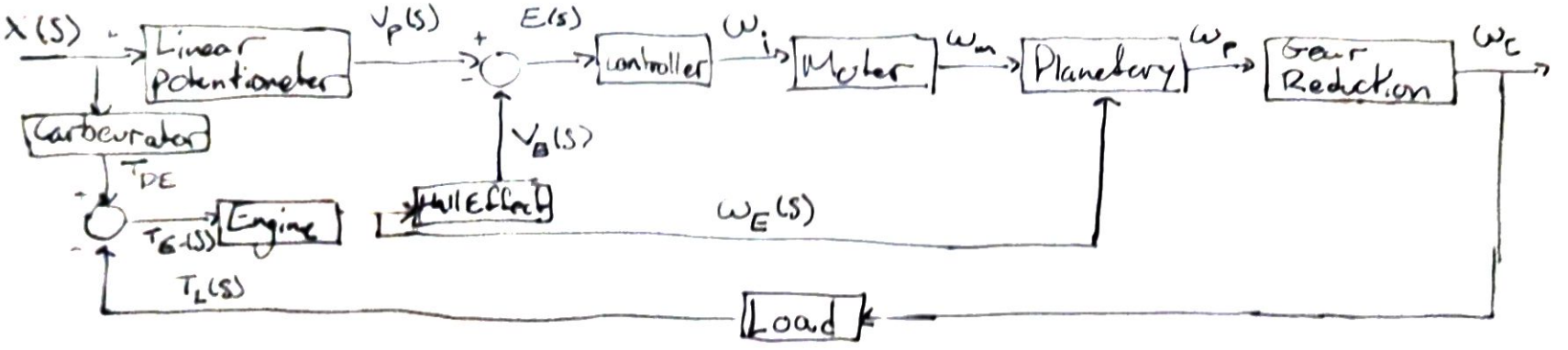

- $X(s)$ = Pedal Displacement
- $V_p(s)$ = Voltage Proportional to pedal displacement
- $E(s)$ = Error Speed
- $\omega_i(s)$ = Input Motor Speed
- $\omega_m(s)$ = Output motor speed
- $\omega_p(s)$ = Ring Gear Output speed
- $\omega_c(s)$ = Speed of the Vehicle
- $T_L(s)$ = Torque from Resistant Load
- $T_E(s)$ = Engine Torque
- $T_{DE}(s)$ = Desired Engine Torque
- $\omega_e(s)$ = Engine speed
- $V_E(s)$ = Voltage proportional to engine speed

* First Iteration with lossless gears
* Motor Design first
* Load and Carbeurator acts as scalars
* Need to understand Sensor changes in
* Controller is undetermined, will be decided upon later due to constraints and requirements from each sub-system