1-3 상세내용

1) 자동차 기능의 이벤트

자동차의 기본적인 기능을 구현하기 위함

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```
public void frontmove()
{
    for (int i = 0; i < wheels.Length; i++)
    {
        float h = 1f;

        if(mheac == move_head.Back)
        {
            h = -1f;
        }

        wheels[i].motorTorque
        = Input.GetAxis("Vertical")
        * tireMoter_Power * h;
        if(Verticalcheck && tireMoter_Power < 1500)
        {
            tireMoter_Power += 0.1f;
        }
        else if(Horizontalcheck)
        {
            tireMoter_Power -= 0.1f;
        }

        tire[i].transform.Rotate(Vector3.right,
        wheels[i].motorTorque * 0.01f);
    }
}

public void steering()
{

    for (int i = 0; i < 2; i++)
    {
        wheels[i].steerAngle
        = Input.GetAxis("Horizontal")
        * tireangle_Power * 0.8f;

        streering[i].transform.localRotation
       = Quaternion.Euler(0, wheels[i].steerAngle, 0);
    }
}
```

브레이크

```
public void brake()
{
    if(Input.GetKey(KeyCode.Space))
    {
        Player_rigidbody.drag = 1f;
        Player_rigidbody.angularDrag = 1f;

        FRFrictionCurve.stiffness = number;
        FLFrictionCurve.stiffness = number;
        HRFrictionCurve.stiffness = number;
        HLFrictionCurve.stiffness = number;
        if(number >= 1.0f)
        {
            number = 1;
        }

        wheels[2].forwardFriction = FRFrictionCurve;
        wheels[2].sidewaysFriction= FLFrictionCurve;
        wheels[3].forwardFriction = HRFrictionCurve;
        wheels[3].sidewaysFriction = HLFrictionCurve;

        for(int i = 1; i < wheels.Length; i++)
        {
            wheels[i].brakeTorque = 10000000f;
        }
    }
    else
    {
        Player_rigidbody.drag = 0f;
        Player_rigidbody.angularDrag = 11f;

        FRFrictionCurve.stiffness = 1f;
        FLFrictionCurve.stiffness = 1f;
        HRFrictionCurve.stiffness = 1f;
        HLFrictionCurve.stiffness = 1f;

        wheels[2].forwardFriction = FRFrictionCurve;
        wheels[2].sidewaysFriction = FLFrictionCurve;
        wheels[3].forwardFriction = HRFrictionCurve;
        wheels[3].sidewaysFriction = HLFrictionCurve;
        for(int i = 0; i < wheels.Length; i++)
        {
            wheels[i].brakeTorque = 0f;
        }
    }
}
```