



Terjadi Error saat disimulasikan, robot mengalami looping bergerak lalu bergerak terlalu cepat

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#include <webots/DistanceSensor.hpp>
#include <webots/Motor.hpp>
#include <webots/Robot.hpp>
#include <webots/Keyboard.hpp>
#include <webots/GPS.hpp>
#include <webots/InertialUnit.hpp>
#include <webots/Camera.hpp>

#define TIME_STEP 64
using namespace webots;

int main(int argc, char **argv) {
    Robot *robot = new Robot();
    Keyboard kb;
    DistanceSensor *ds[2];

    char dsNames[2][10] = {"ds_right", "ds_left"};
    for (int i = 0; i < 2; i++) {
        ds[i] = robot->getDistanceSensor(dsNames[i]);
        ds[i]->enable(TIME_STEP);
    }
    Motor *lr;
    lr=robot->getMotor("linear");

    Motor *rm;
    rm=robot->getMotor("rm");

    Camera *cm;
```

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cm=robot->getCamera("camera");
cm->enable(TIME_STEP);

Motor *wheels[4];
char wheels_names[4][8] = {"wheel1", "wheel2", "wheel3", "wheel4"};
for (int i = 0; i < 4; i++) {
    wheels[i] = robot->getMotor(wheels_names[i]);
    wheels[i]->setPosition(INFINITY);
    wheels[i]->setVelocity(0.0);
}

kb.enable(TIME_STEP);
double leftSpeed = 0.0;
double rightSpeed = 0.0;
double linear=0.0;
double rotate=0.0;
while (robot->step(TIME_STEP) != -1) {
    int key=kb.getKey();

    if (key==315){
        leftSpeed = 1.0;
        rightSpeed = 1.0;
    } else if (key==317){
        leftSpeed = -1.0;
        rightSpeed = -1.0;
    } else if (key==316){
        leftSpeed = 1.0;
        rightSpeed = -1.0;
    } else if (key==314){
        leftSpeed = -1.0;
        rightSpeed = 1.0;
    } else {
        leftSpeed = 0.0;
        rightSpeed = 0.0;
    }
    wheels[0]->setVelocity(leftSpeed);
    wheels[1]->setVelocity(rightSpeed);
    wheels[2]->setVelocity(leftSpeed);
    wheels[3]->setVelocity(rightSpeed);
    if (key==87 && linear<0.19){
        linear += 0.005;
    } else if (key==83 && linear>0){
        linear += -0.005;
    } else {
        linear+=0;
    }
    lr->setPosition(linear);
    std::cout<<key<<std::endl;
    if (key==65 && rotate<1.57){
        rotate += 0.05;
    } else if (key==68 && rotate>-1.57){

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rotate += -0.05;
}else {
rotate+=0;
}
rm->setPosition(rotate);

}
delete robot;
return 0; // EXIT_SUCCESS
}
```