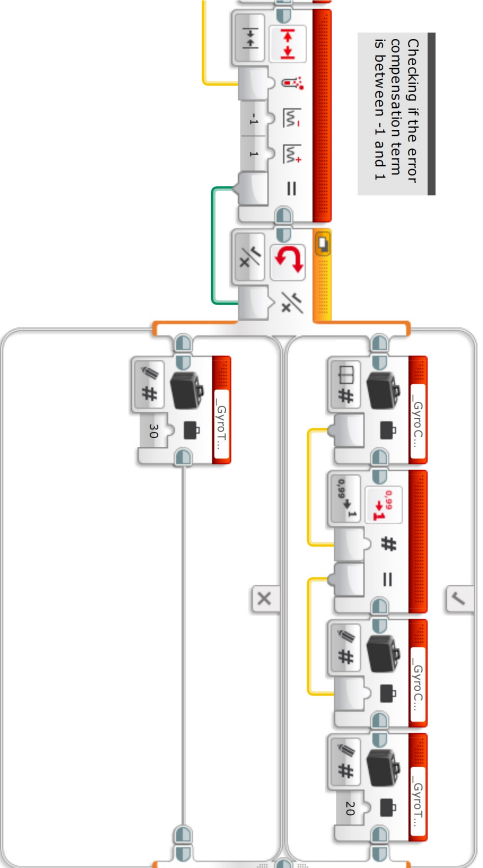
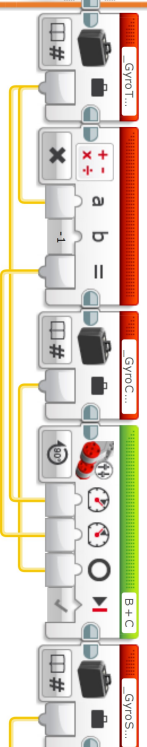


Checking if the error  
compensation term  
is between -1 and 1



Two wheel turn using MoveTank  
block by amount of degrees  
computed by PID controller



Continue the loop only until there  
is an exact match of the measured  
angle with the target angle

