

Turn the robot using a continuous loop until it moves to the target angle

GyroSpinTurn MyBlock uses Gyro Sensor and PID_Controller_Code MyBlock to turn the Robot to the desired angle

Input: Degrees
(Target turn angle measured in degrees)

Calculate error (deviation from target angle)

Error compensation using PID controller gain
Kp: Proportional gain
Ki: Integral gain to accumulate error and eliminate state error (enables exact angle match)
Kd: Differential gain to provide damping and reduce overshoots

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

