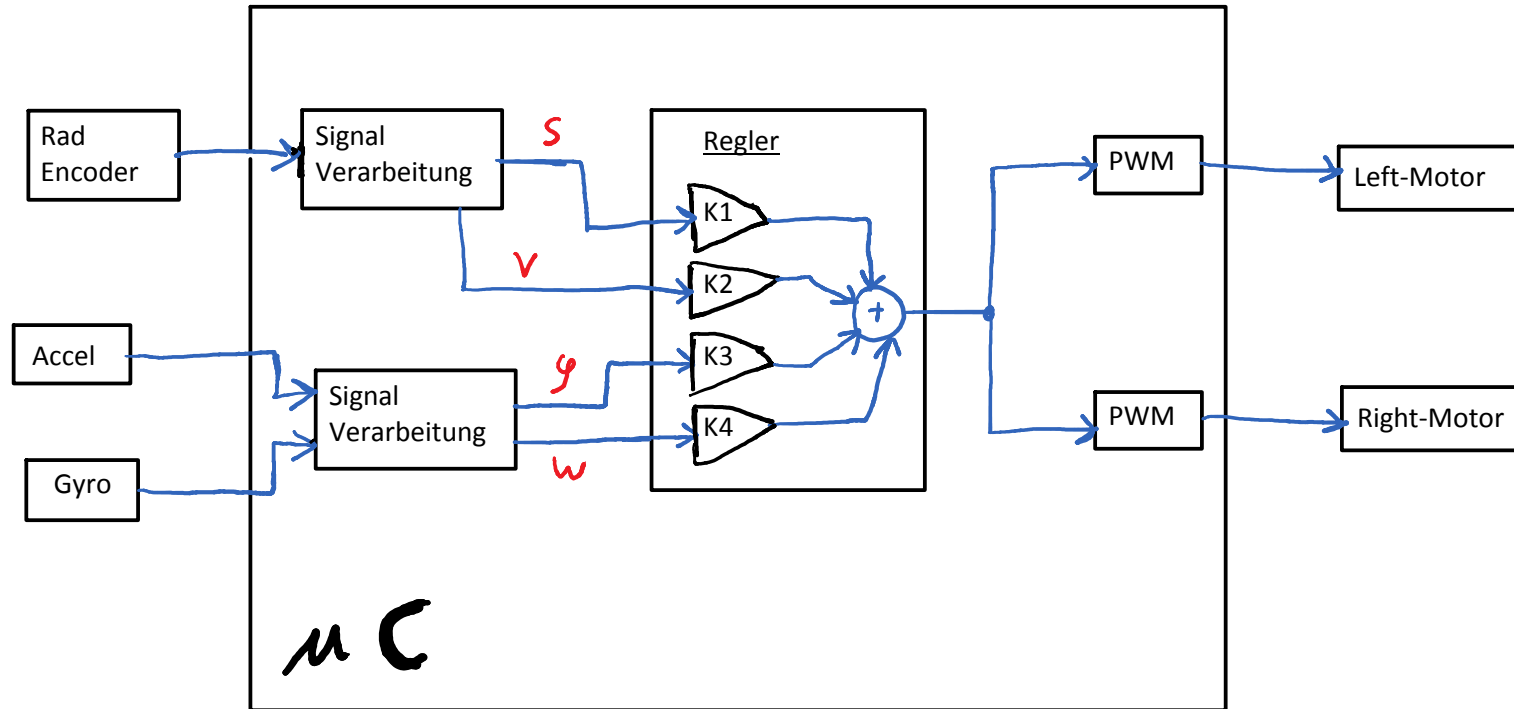
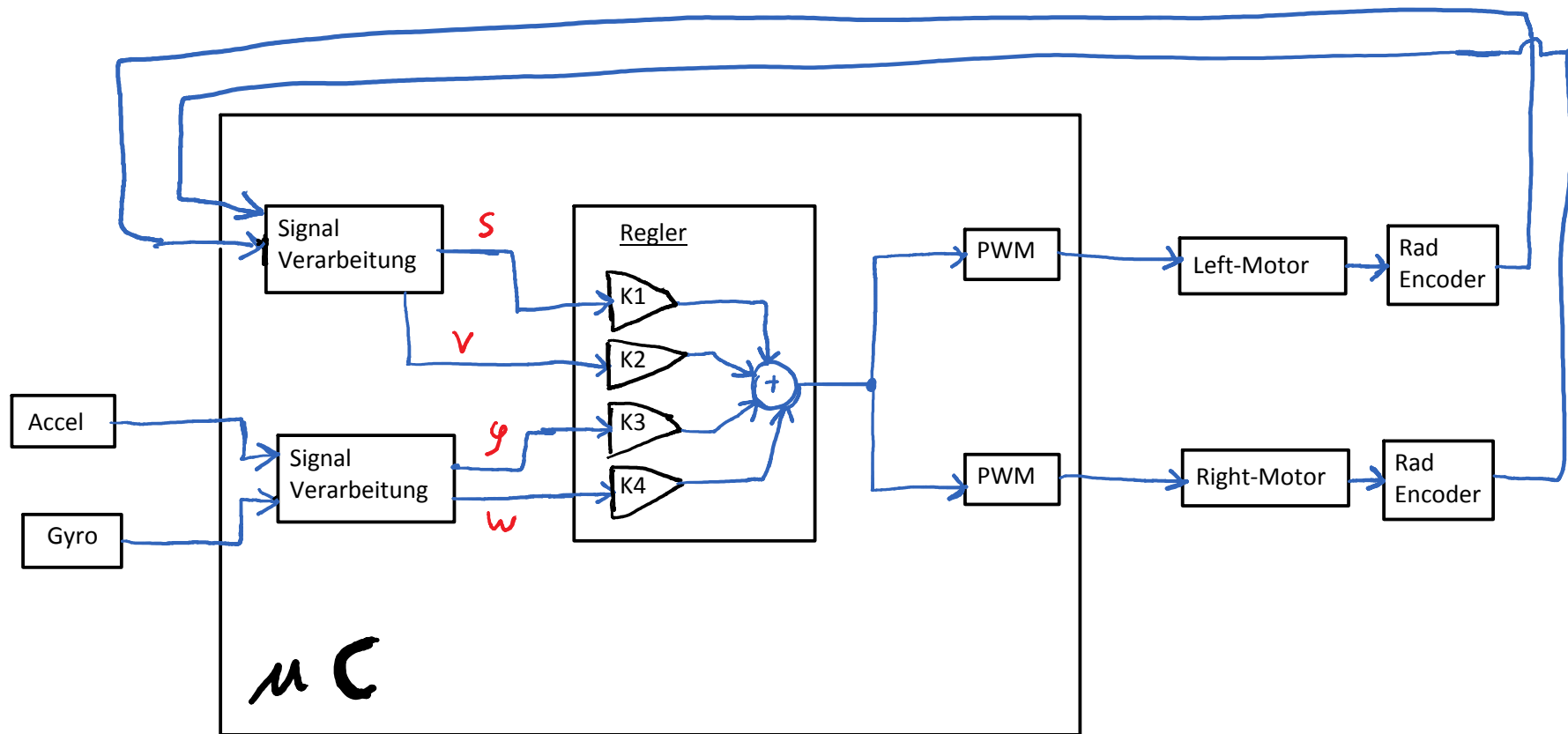
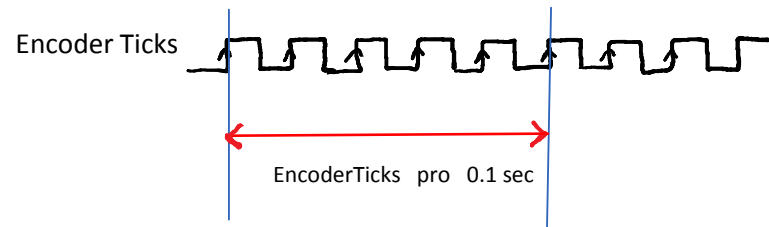


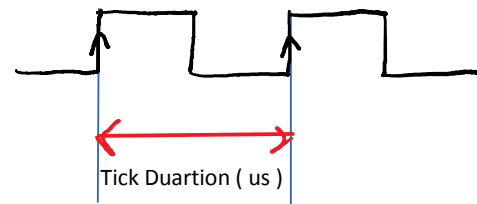
Balancing Robot

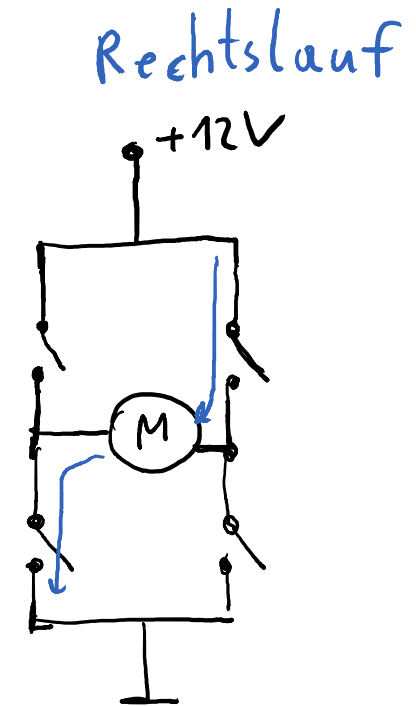
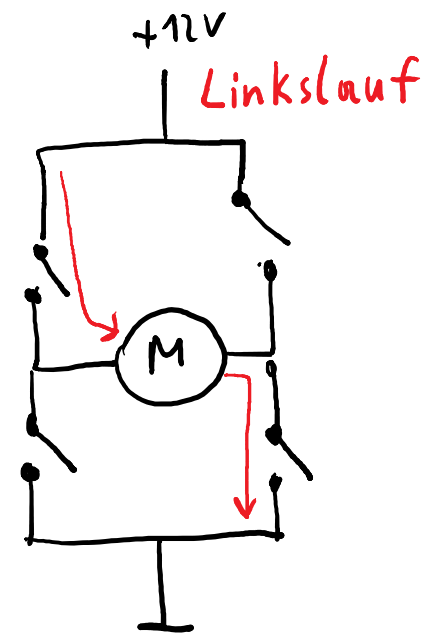
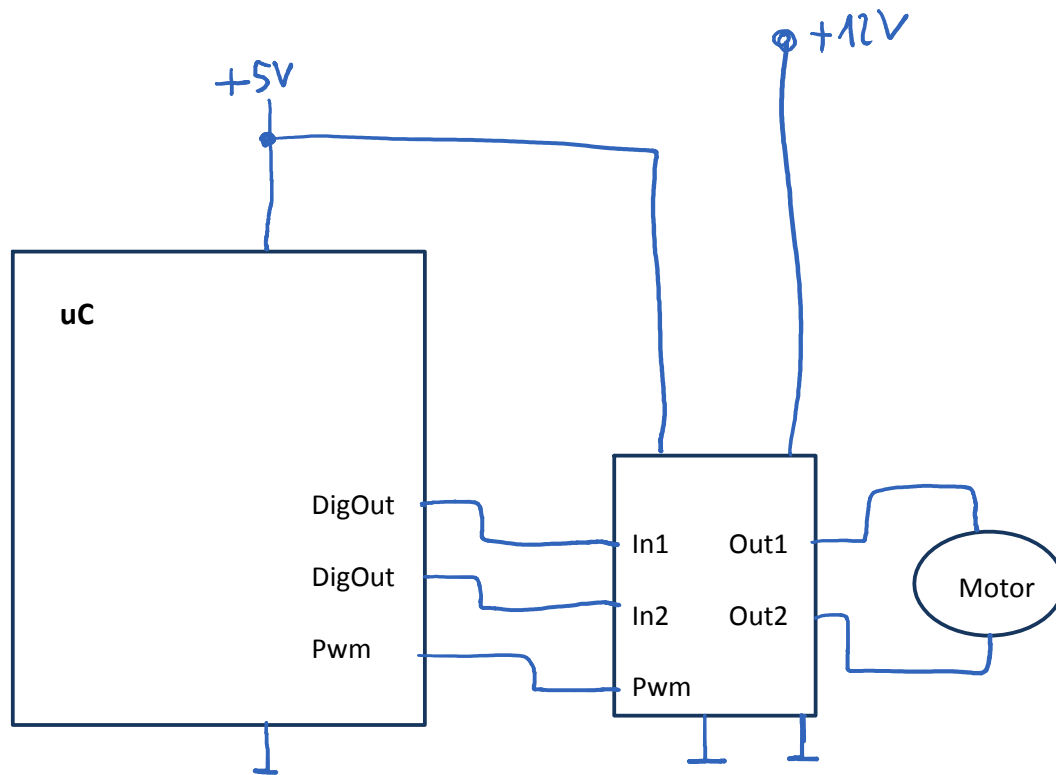
Balancing Robot

Die 2 Möglichkeiten zur Drehzahlmessung

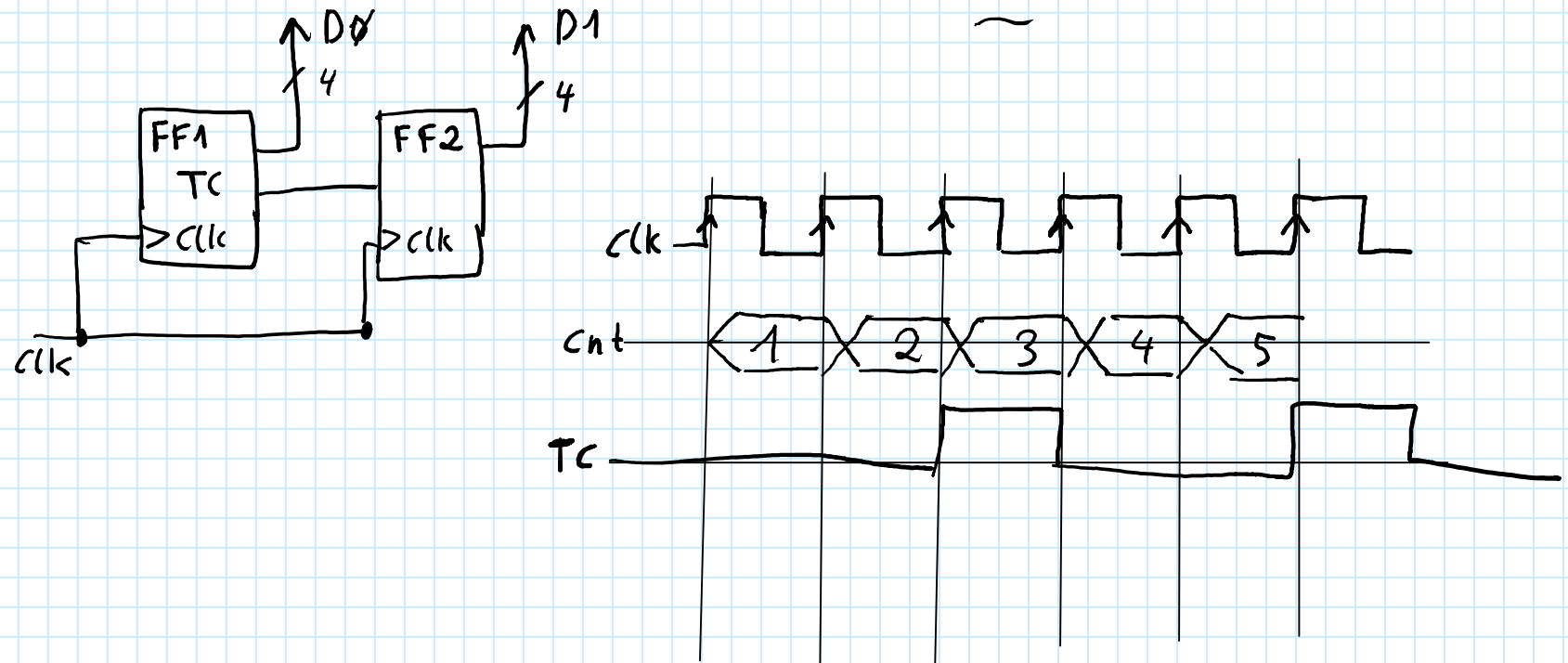
UPM == Ticks pro 0.1 sec

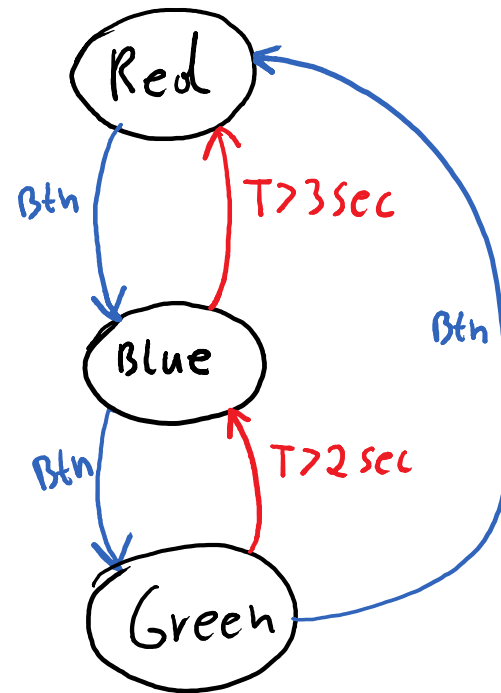
UPM == $1 / \text{TickDuration}$

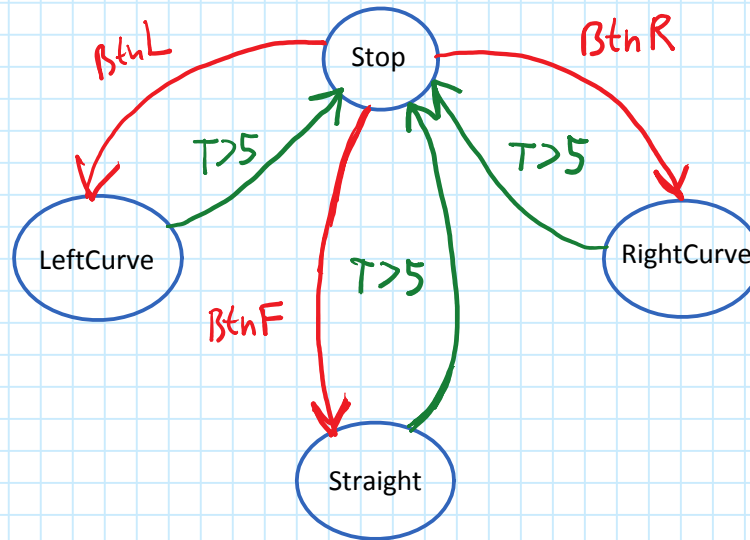




Schalter werden mit der **PWM-Frequenz** und **DutyCycle** geschaltet



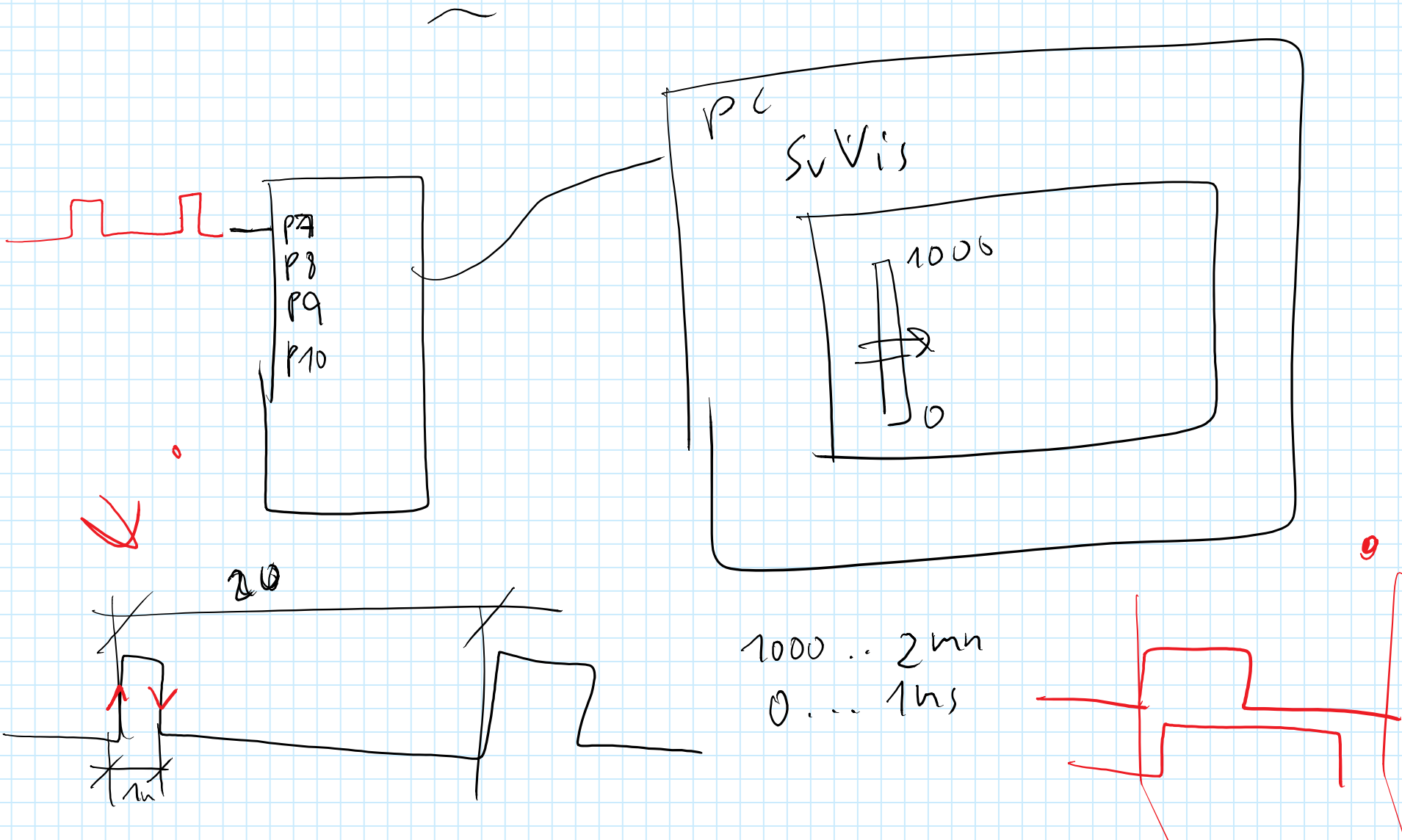


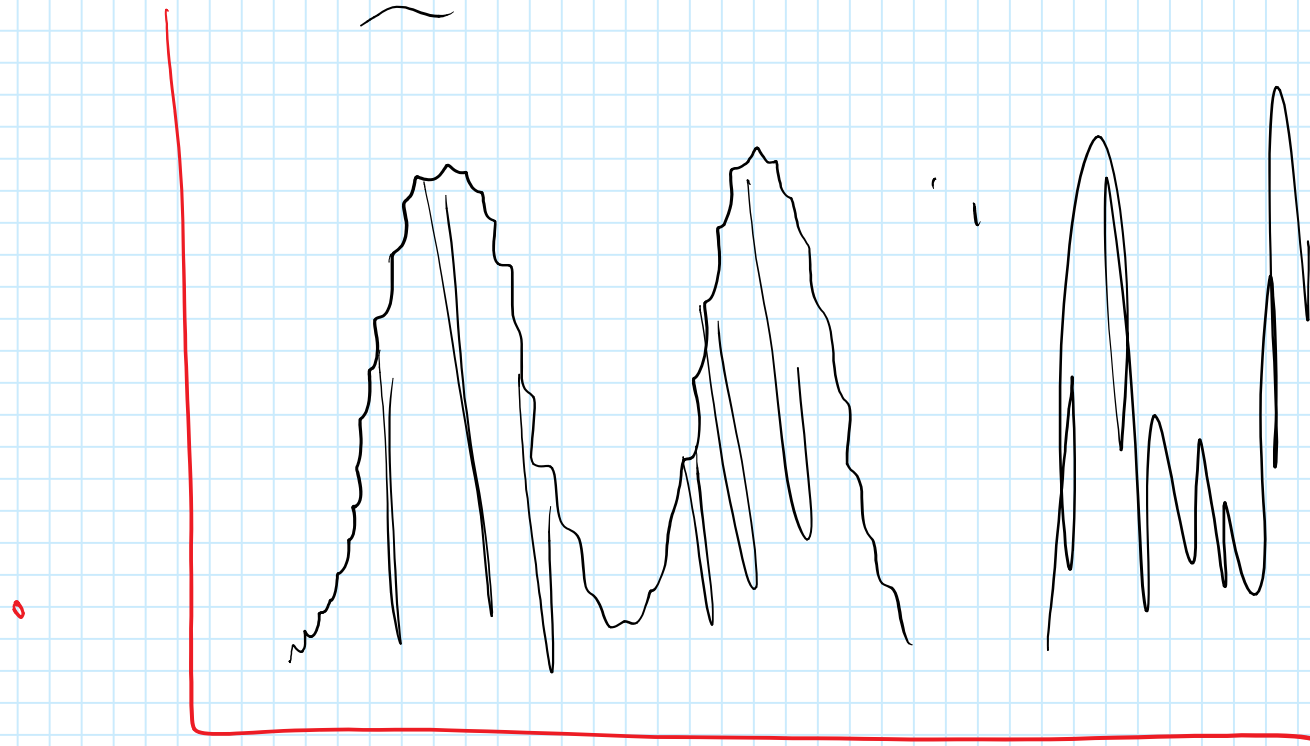


LeftCurve:
Links Blinken

RightCurve:
Rechts Blinken

Straight
Beide vorne Blinken





$D1, D2, D3$

$$D1 = 1$$

$$D2 = 0$$

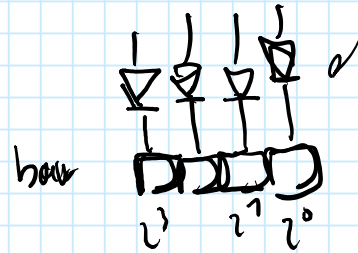
$$D3 = 1$$

$$D4 = 0$$

byt Value

12

ככככככככ



$$b_{uv} = 0$$

$$b_{ov} = 1$$

$$b_v = 2$$

$$b_i = 3$$