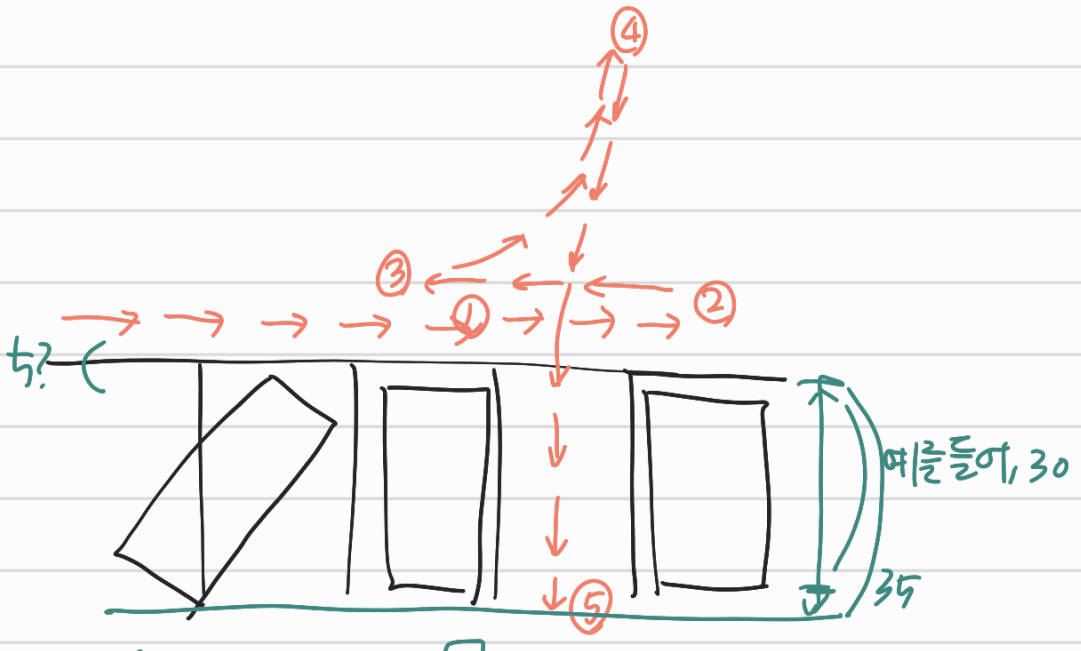
기본 주차 트랙



① if (앞의 US 거리 > 30)

space_time = ustime

② if (앞의 US 거리 < 30)

space_time2 = ustime

if (space_time2 − space_time > 5)

how_parking = 1

motor_state = Backward

parking_time = ustime

× 1.5배

③ while(1)

if (ustime − parking_time > 7)

motor_state = Forward_Left 1

parking_time = ustime

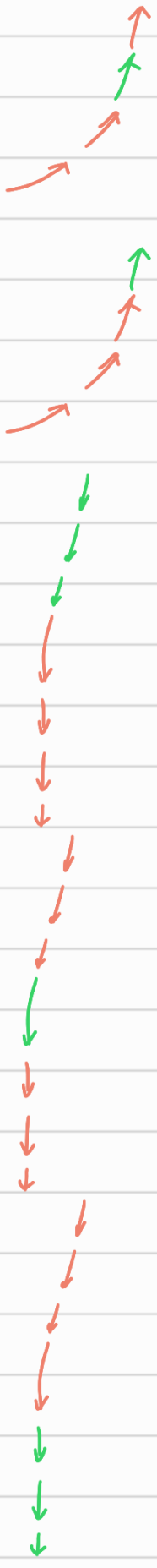
while(1)

if(ustime − parking_time > □)

motor_state = Forward_Left 2

parking_time = ustime

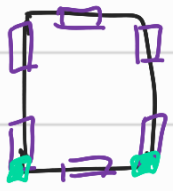
```
while(1)
    if(ustime - parking_time> □)
        motor_state = Forward_Left3
        parking_time = ustime
while(1)
    if(ustime - parking_time > □)
        motor_state = Forward
        parking_time = ustime
④ while(1)
    if(ustime - parking_time > □)
        motor_state = Backward_Right1
        parking_time = ustime

while(1)
    if(ustime - parking_time > □)
        motor_state = Backward_Right2
        parking_time = ustime

while(1)
    if(ustime - parking_time > □)
        motor_state = Backward
        parking_time = ustime
```



퍼지이론 이용하여 정확한 주차

(위의 '기본적인 틀'을 모두 수행한 후 진행)

초음파센서 → US* (ultrasonic) 라인트레이싱 센서 → LT* (line tracing)



front_diff rear_diff

변수 : 왼앞-오른앞 US, 왼뒤-오른뒤 US, 좌LT, 우LT,
왼앞US, 오른앞US, 왼뒤US, 오른뒤US

이상적인 상태 : |front_diff| < 0.5
|rear_diff| < 0.5
||front_diff| - |rear_diff|| < 0.5 ?
좌LT, 우LT : 0 되도록 (단순 차선 밟을때 X, 뒤 방지턱 닿았을 때 O)

RD \ FD	LL	L	C	R	RR
LL					
L					
C					
R					
RR