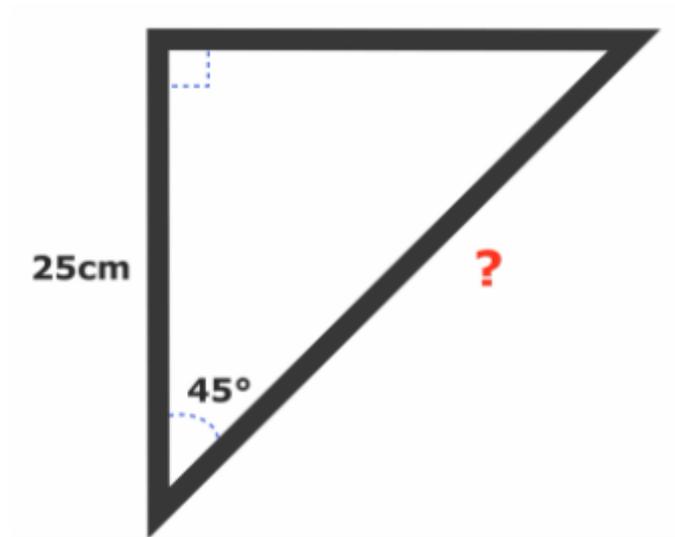
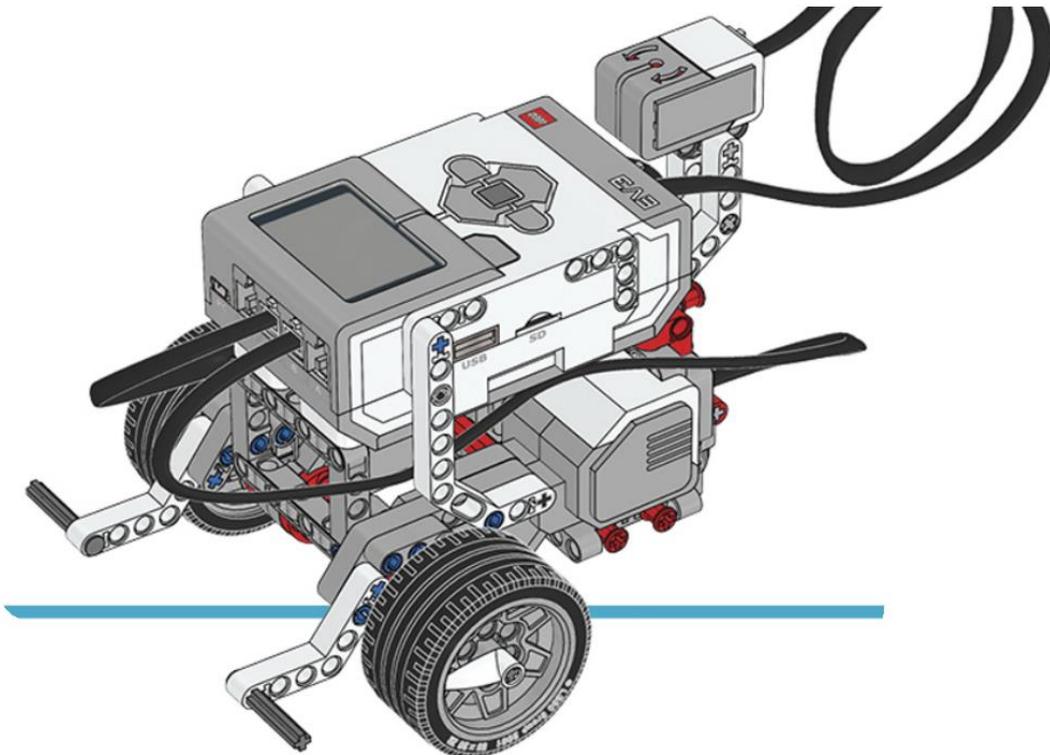


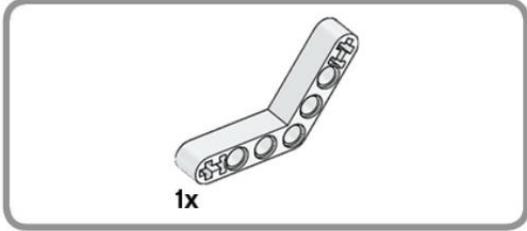
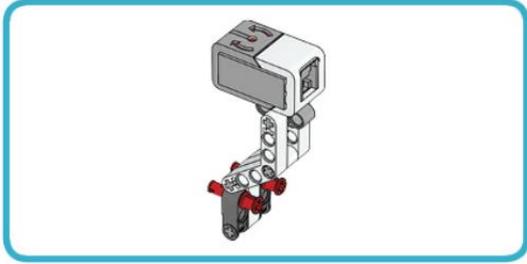
Matemática - Avanzada

Utilizaremos la trigonometría para navegar en la Base Motriz.

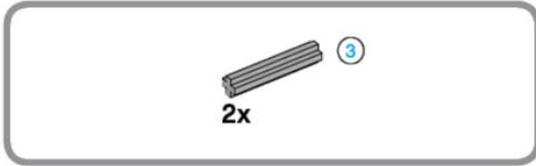


Tenemos que montar el Giro sensor.

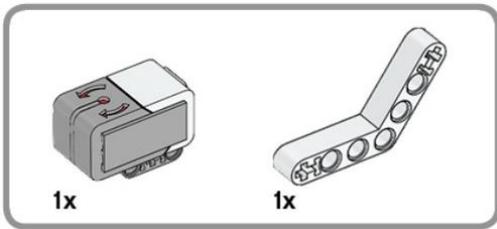
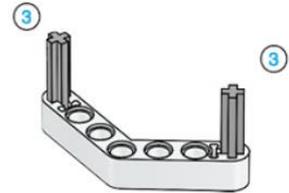




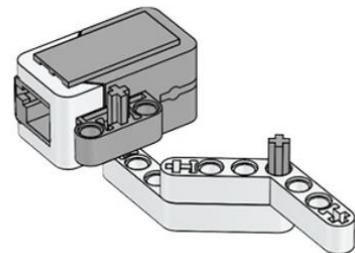
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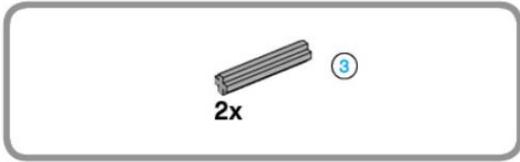


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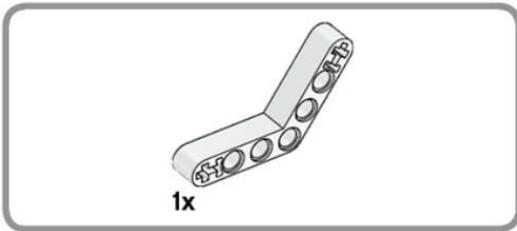
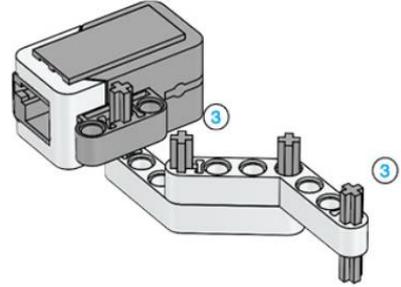


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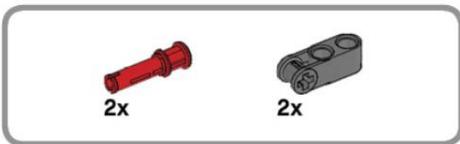
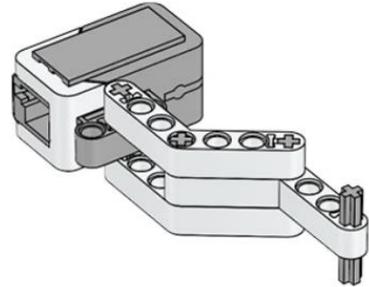




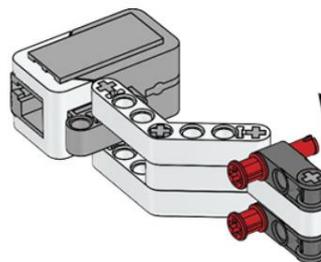
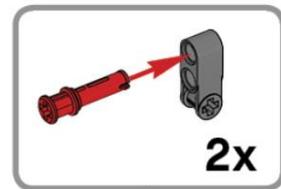
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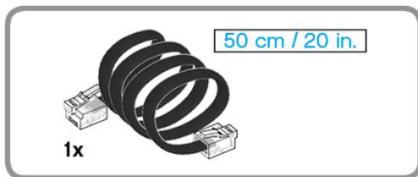
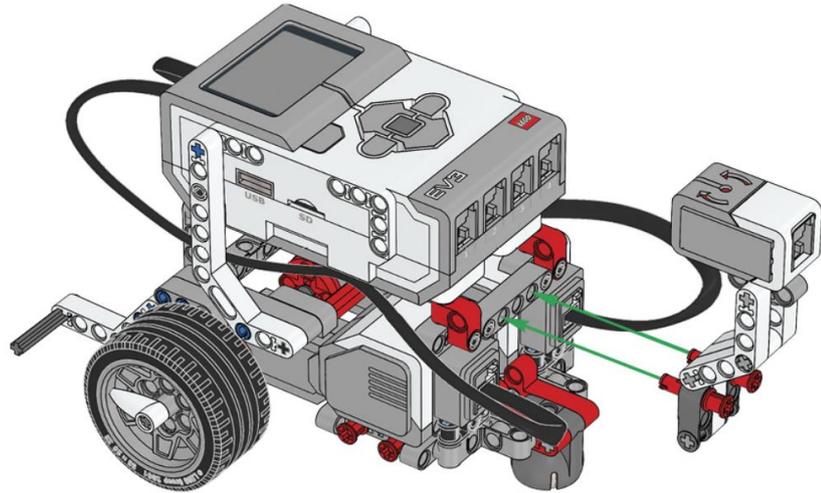
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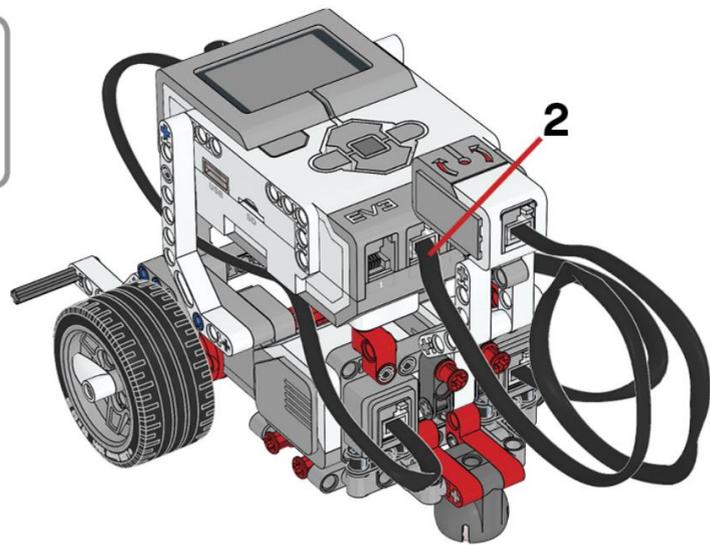
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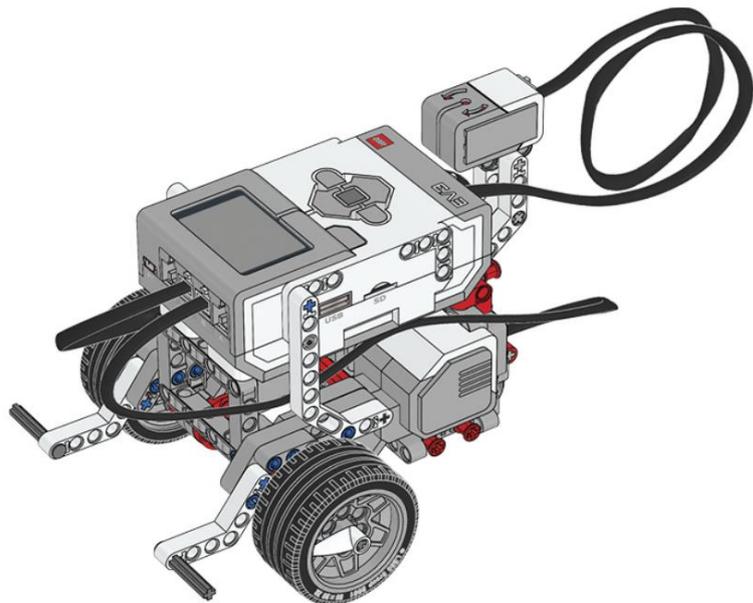
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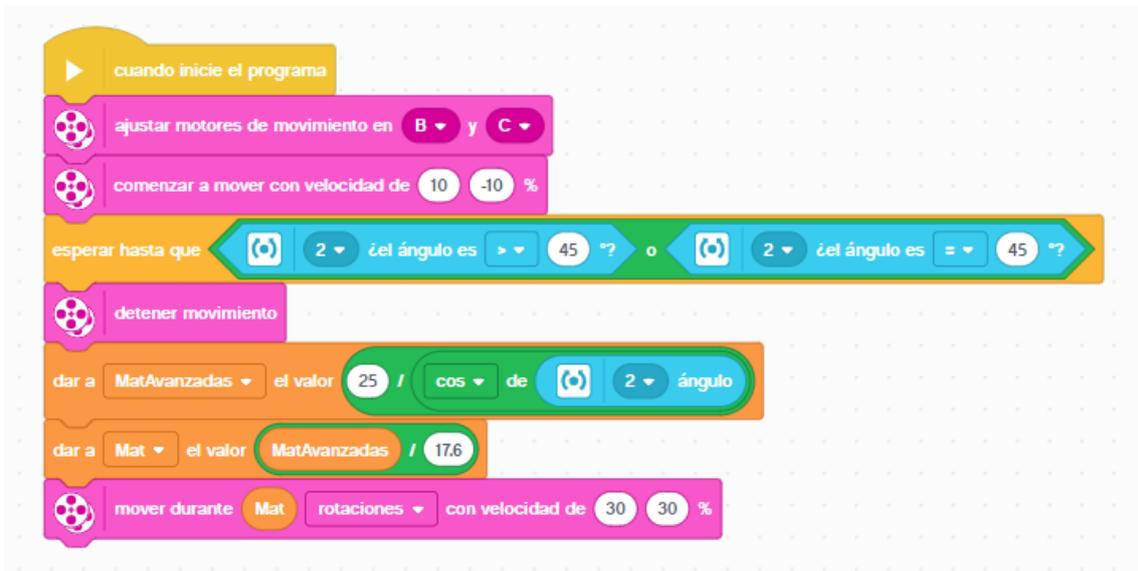
8



9



Este es el resultado:



Definimos los motores de dirección B y C.

Comenzar a moverse con una potencia 10 y de -10 (rotará sobre si mismo a una velocidad muy corta)

Esperar hasta que el valor del giro sensor sea mayor o igual a 45.

Entonces se para el motor.

A la variable MatAvanzadas le pasamos la siguiente formula $25 / \cos(\text{valor giro sensor})$

A la variable Mat le pasamos la siguiente formula $\text{MatAvanzadas} / 17,6$ (Perímetro de la rueda)

Movemos nuestro robot hacia adelante a una potencia del 30% en ambas ruedas con un numero de rotaciones del valor de la variable Mat.

Este tiene que ser el resultado:

