

Problem Wk.5.3.4: Wall Follower Model

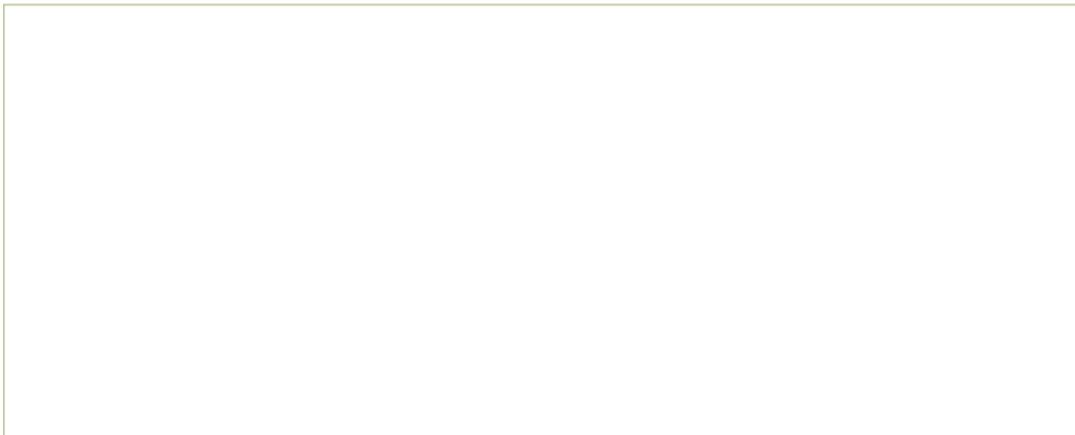
Use `sf.R`, `sf.Gain`, `sf.Cascade`, `sf.FeedbackAdd` and `sf.FeedbackSubtract` to construct the wall-finder robot system function. These procedures are documented in [Module sf](#) in the [software documentation](#).

Define a Python procedure called `wallFollowerModel` that takes three arguments:

- the proportional gain, k_p , applied to the error.
- the time step duration τ
- the translational velocity v

and which returns a system function for a system whose input is the desired distance and whose output is the actual distance to the wall.

You can debug these in Idle in the `designLab05Work.py` file.



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