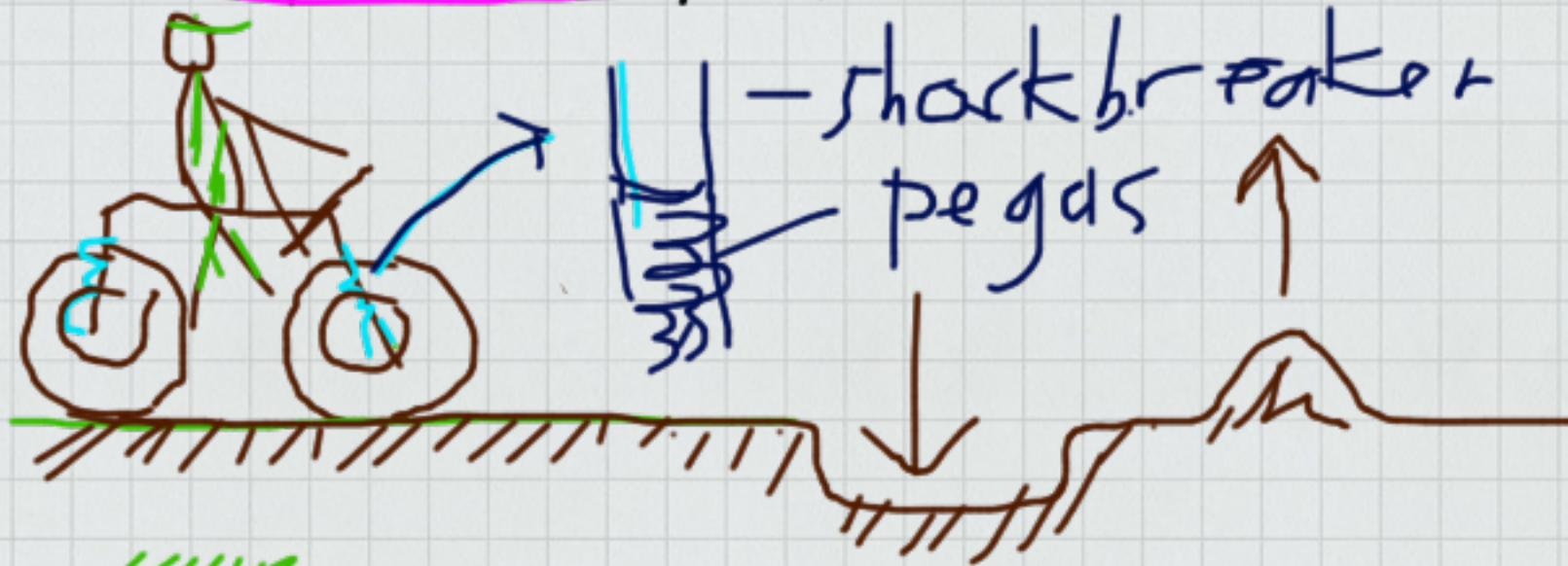


* PROJECT 2 : Sistem Suspensi Sepeda Motor

Dikumpulkan: 16/10/15



guncangan
pengendalian

$$x(t) = \frac{1}{2}(x_d(t) + x_b(t))$$

↑
bela.
guncangan
roda depan

