Read Me: Overshoot

- The following are the input arguments for the scene:

start configuration: [0.000,-0.500,0,0.368,-0.123,-0.257,-0.254,0,0,0,0,0,0];
wheel speed limit=1.4;
joint angle limit=50;
time step=0.01;
Kp=1.4;
Ki=1;

- The overshoot can be observed at the end of segment 1, when the gripper arrives at the standoff position.
- The code uses Proportional and Integral control along with feed forward control.
- The Error plot, Error data file and the Trajectory file (.csv) are in the folder.
- The Video has been sped up and slowed down at times. The original motion can be viewed by running the .csv file in v-rep.