

Read Me: Best

- The following are the input arguments for the scene:

start configuration: [-0.147,-0.580,-0.095,-0.393,-0.123,-0.368,-0.193,0,0,0,0,0];

wheel speed limit=1;

joint angle limit=50;

time step=0.01;

Kp=1.6;

Ki=0.4;

- 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.