

Read Me: New_Task

- The following are the input arguments for the scene:

start configuration: [0.000,-0.500,0.1,0.368,-0.123,-0.257,-0.254,-0.123,0,0,0,0];

wheel speed limit=1.4;

joint angle limit=50;

time step=0.01;

Kp=1.6;

Ki=0.3;

- 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.