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| **Starting Postures Final Project RC2** |

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| ***RUN*** | ***Robot 1*** | ***Robot 2*** | ***Robot 3*** | ***Rendez-Vous*** |
| Position Regulation | [6, 6, pi] | [6, 1, pi/2] | [1, 3, -pi/2] | [4.33, 3.33, \*] |
| Posture Regulation | [6, 6, pi] | [6, 1, pi/2] | [1, 3, -pi/2] | [4.33, 3.33, 1.047] |
| OF with change of variable | Start from Position Regulation | | | / |
| SF with exact linearization | Start from Position Regulation | | | / |
| OF with further Derivatives | Start from Position Regulation | | | / |
| SF with approx. linearization | Start from Position Regulation | | | / |
| Switching 1 | [1, 6, pi] | [5, 2, pi/6] | [3, 3, -pi/4] | [3, 3.66, 0.96] |
| Switching 2 | [1, 6, pi] | [6, 6, pi] | [3, 6, pi] | [3.33, 5.5, pi] |
| Switching 3 | [1, 4, -pi/2] | [3, 6.5, pi/2] | [3, 4.5, pi/4] | [2.33, 5, 0.262] |
| Switching 4 | [6, 6, -pi/2] | [4, 2, -pi/3] | [1, 1, 0] | [3.66, 3, -0.873] |
| Switching 5 | [1, 6, 0.66\*pi] | [1, 3, pi] | [1, 1, pi] | [1.5, 3.33, 2.7925] |
| Switching 6 | [3, 3, pi/7] | [5, 4, -pi] | [1, 6, -pi/8] | [3, 4.33, -1.0285] |
| Switching 7 | [1, 6, -pi/4] | [6, 1, pi/6] | [4, 6, pi] | [3.66, 4.33, 0.96] |
| Switching 8 | [2.5, 6, pi/4] | [2, 1, pi/2] | [1, 6, -pi/6] | [1.833, 4.33, 0.6109] |