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Implementación de robótica inteligente

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Actividad 5.1: Control de Posición

# Análisis comparativo

## (1, 2)

### K = [10 0; 0 10]

### K = [5 0; 0 5]

### K = [15 0; 0 15]

## (3, 7)

### K = [10 0; 0 10]

### K = [5 0; 0 5]

### K = [15 0; 0 15]

## (6, 0)

### K = [10 0; 0 10]

### K = [5 0; 0 5]

### K = [15 0; 0 15]

## (-4, 5)

### K = [10 0; 0 10]

### K = [5 0; 0 5]

### K = [15 0; 0 15]

## (-6, 0)

### K = [10 0; 0 10]

### K = [5 0; 0 5]

### K = [15 0; 0 15]

## (-1, 0)

### K = [10 0; 0 10]

### K = [5 0; 0 5]

### K = [15 0; 0 15]

## (-7, -7)

### K = [10 0; 0 10]

### K = [5 0; 0 5]

### K = [15 0; 0 15]

## (-2, -4)

### K = [10 0; 0 10]

### K = [5 0; 0 5]

### K = [15 0; 0 15]

## (- 0.5, -0.5)

### K = [10 0; 0 10]

### K = [5 0; 0 5]

### K = [15 0; 0 15]

## (1, -3)

### K = [10 0; 0 10]

### K = [5 0; 0 5]

### K = [15 0; 0 15]

## (3, -5)

### K = [10 0; 0 10]

### K = [5 0; 0 5]

### K = [15 0; 0 15]

## (8, 0)

### K = [10 0; 0 10]

### K = [5 0; 0 5]

### K = [15 0; 0 15]

## (0, -3)

### K = [10 0; 0 10]

### K = [5 0; 0 5]

### K = [15 0; 0 15]

## (0, 9)

### K = [10 0; 0 10]

### K = [5 0; 0 5]

### K = [15 0; 0 15]

## (0, -1)

### K = [10 0; 0 10]

### K = [5 0; 0 5]

### K = [15 0; 0 15]

## (-5, -10)

### K = [10 0; 0 10]

### K = [5 0; 0 5]

### K = [15 0; 0 15]

## (7, -7)

### K = [10 0; 0 10]

### K = [5 0; 0 5]

### K = [15 0; 0 15]

## (3, -1)

### K = [10 0; 0 10]

### K = [5 0; 0 5]

### K = [15 0; 0 15]

## (- 10, -10)

### K = [10 0; 0 10]

### K = [5 0; 0 5]

### K = [15 0; 0 15]

## (10, 9)

### K = [10 0; 0 10]

### K = [5 0; 0 5]

### K = [15 0; 0 15]