Arguments of discussion for the presentation:

* Intro
* Goal and how we plan to reach it
* Unicycle model
* Consensus
* Little talk about the theory + (one step consensus)
* Cartesian
* Graphics: pg 47
* No control over orientation
* Unwrap ? (graphics?)
* Notice it ends with random orientations
* Posture
* Implementation: reference offset (graphics?)
* Implementation: unwrap (graphics?)
* Singularity in corrected (explain why we didn’t use the one with singularity)
* Notice orientations go to 0
* Why do we choose posture rather than Cartesian?
* Controller Switch
* Implementation: initial conditions must be passed when switching
* Testing procedure
* Various tests and ideas ()
* Graphics: flowchart
* Controllers
* Control laws
* Linear
* Fixed control law
* Non-linear
* Time varying control law
* How does the parameter change the control law
* cannot be both zero
* Sagittal
* Implementation: derivatives
* No differential flatness
* (what happens when b changes?)
* Double derivative
* Implementation: derivative
* Smooth and persistent trajectory
* No differential flatness
* Conclusions
* Test results comparison
* Best choice for controller