

Controller Information and Results

Controller Type

- **Feedforward + Proportional (P) + Integral (I) Controller**

Feedback Gains

- **K_p**: Identity Matrix
- **K_i**: 3 * Identity Matrix

Performance Summary

- **Overshoot**: Visible overshoot
- **Response Speed**: Fast
- **Accuracy**: Successfully picks and places

Notes

- This setup represents the overshoot-case scenario, where an K_i term is purposely added to show a slightly less effective controller
- The error twist response can be seen in the plot, where each velocity component is plotted over time, and overshoot and oscillation is shown
- By the end of step 1 of the trajectory, there is no error and the velocities converge