

NewTask Case

Controller type: PI Control

Feedback Gains: $K_i = 0.25$ $K_p = 1$

$$T_{initial} = \begin{bmatrix} 0 & -1 & 0 & 0 \\ 1 & 0 & 0 & 1 \\ 0 & 0 & 1 & 0.025 \\ 0 & 0 & 0 & 1 \end{bmatrix}$$

$$T_{final} = \begin{bmatrix} 1 & 0 & 0 & -1 \\ 0 & 1 & 0 & 0 \\ 0 & 0 & 1 & 0.025 \\ 0 & 0 & 0 & 1 \end{bmatrix}$$