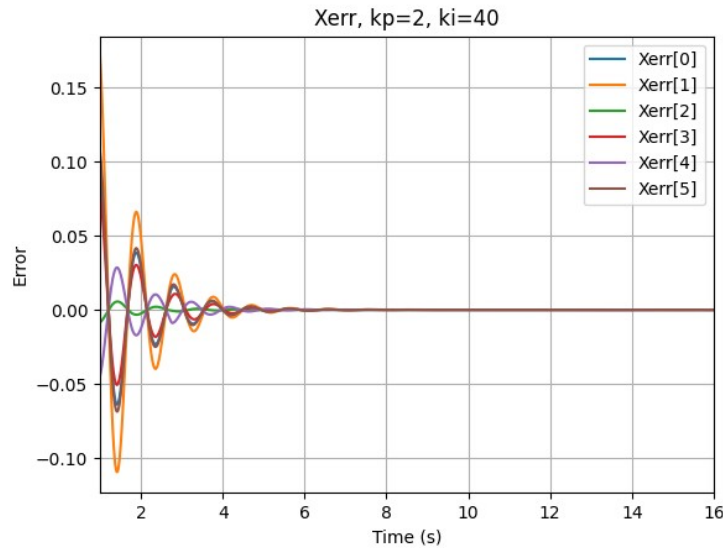


Robotic Manipulation – Final Project - Overshoot

For this part, I tuned the controller's proportional and integral gains in such way that there will be an intentional overshoot.

I used PI controller with feedback gains of $K_p = 2$ and $K_i = 40$.

The following graph shows the error between the current and the desired states as function of time:



We can see that we got a big overshoot with fast convergence to zero – as expected from a high integral gain system.

In this folder you can find the csv files of the robot configurations throughout the motion and the motion error. You can also find the logfile produce when running the code and the simulation video.