Individual Report

I did the evaluation of the controller in the report with discussion and analysis in terms of steady state error, damping ratio, rise time, settling time and overshoot by modifying the rosbag plotting script to have a better view on the step response of the controller. I handled the write-up of this part in the report.

Madeline did trajectory generation and analysis with the write-up in the report and we use her codes in the second lab session. She also plot all the experimental trajectories from the second lab session using rosbag and discussed the error between the simulation and the real-time data.

Anthony did the formulation and derivation of the non-linear geometric controller we used for this lab. We also use his code for the first lab session.