Leon Ampah

Alex Waweru

Ayomide Adelaja

**LAB REFLECTION**

The point of this exercise was to grasp the feel of the different types of feedback control namely, bang-bang, p-control, pd-control and pid-control. One major thing we noticed in the course of this task was that as the content of the output became more complex i.e. when we considered the integral and the derivative of the error the motion of the robot became smoother as compared to the motion in the bang-bang control. Some of the challenges we faced during the trial included finding a suitable values for constant of proportion, constant of integration and constant of differentiation and adjusting the speed of individual motors to make the turns look seamless.