

Controller Type: Feedforward + PI Controller

$K_p = 5$

$K_i = 0.2$

Initial Configuration: $(x, y, \theta) = (0.5 \text{ m}, 0 \text{ m}, 0 \text{ rad})$

Final Configuration: $(x, y, \theta) = (0 \text{ m}, -0.5 \text{ m}, -\pi/2 \text{ rad})$