Overshoot README

Type of Controller:

feedforward-plus-PI control

Feedback Gains:

$$K_p = 10$$
$$K_i = 10$$

K_p
- If too large will cause instability
- Increase to speed up control system response

K_i
- Drives steady state error to 0
- Response exhibits overshoot and oscillation as increased

The initial trajectory is seven seconds long and the error is driven to zero within 2 seconds.