Supervisor Meeting

Friday, 05th of May 2017

Status

- Boat up and running again.
- We can move the boat remotely through the internet.

Robust Section Comments

- Remember to put the references in the form of numbers.
- Paragraph in page 28 is repeated.
- Monte Carlo simulations with disturbances and parameters variations could be a good idea to test the controllers. Run several step responses and check the behavior.
- Do the same simulations with the LQR and compare them.
- Check the inputs in both controllers because they are also in the performance function.
- Maybe the LQR requires less energy and worse response but both fulfill their requirements.

Waypoint Section Comments

- The path is done by using straight lines between points, but we do not need to hit the points.
- It is a mixture between waypoints and path following, so explain the whole approach better.
- The path outside the area is not important.
- Show that the algorithm will always converge to the path mathematically.
- We could also prove that with constant disturbance there will be a constant offset.
- Plot of how much are we deviating from the line (the distance) and how it goes to 0.

Next Meeting

Thursday, 11th of May at 13:00