

## Demonstration 2 Prep

Kieran Cosgrove

To prep for the demonstration, I updated the command list to match what is outlined for the lab:

```
commandTimes = [ 0, 0, 0, 0, 1, 1+run_time, 6+run_time ] #  
Time to send command  
commandData = [OLgain, Kp, Ki, Kd, ref_speed, 0, -ref_speed ] #  
Value to send over  
commandTypes = [ 'f', 'P', 'I', 'D', 'c', 'c', 'c' ] # Type of  
command to send
```

I also set some initial gain values for testing, because it definitely won't be 0:

```
# Closed loop gains  
Kp = 0.1 # Determine units  
Ki = 0.1 # Determine units  
Kd = 0.001 # Determine units  
ref_speed = 300 # rad/s change as needed  
run_time = 1 # time run motor
```