Demonstration 2 Prep

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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