Marco Morales

ME 449 NewTask

Kp used:1.31, Ki used:0.01, Speed limit:15

This objective used feedback forward and a PI controller. For NewTask, a Kp of 1.31 was used and a Ki of 0.01 was used as well. The initial block position and goal position were changed and the robot had to move to the new initial block, pick the block up and then place it in the new goal position, which it successfully completed.

The new Tsc_initial and Tsc_goal are as follows:

Tsc_initial = np.array([[1,0,0,1], [0,1,0,1], [0,0,1,0.025], [0,0,0,1]])

Tsc_goal = np.array([[0,1,0,1], [-1,0,0,-1], [0,0,1,0.025], [0,0,0,1]])