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ME 449 Best

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

This objective used feedback forward and a PI controller. For Best, a Kp of 1.31 was used and a Ki of 0.01 was used as well. Best will result in the robot having no oscillation and picking up the block and placing it with no problems. The error goes to zero after the first trajectory point.