*** 'NewTask' Scenario:

*Initial Cube configuration: (x,y,theta) = (1.5,0.5,0)

*final cube configuration: (x,y,theta) = (1.5,-1.25,-pi/3)

*Initial youbot config:

Chassis Phi	Chassis x	Chassis y	J1	J2	J3	J4	J5	W1	W2	W3	W4	gripper state
0.7	-0.3	0	0	0	0	0	0	0	0	0	0	0

*Controller type: Feedforward + PI

*Gains Kp = 3, Ki = 1

*Speed Limit was set to 2.5*pi rad/sec for both wheels and joints.