

Readme

Type of controller: feedforward-plus-PI

$T_{sc\_initial} = [1 \ 0 \ 0 \ 1; 0 \ 1 \ 0 \ 0; 0 \ 0 \ 1 \ 0.025; 0 \ 0 \ 0 \ 1]$

$T_{sc\_final} = [0 \ 1 \ 0 \ 0; -1 \ 0 \ 0 \ -1; 0 \ 0 \ 1 \ 0.025; 0 \ 0 \ 0 \ 1]$

$K_p = 3.5$

$K_i = 0.5$