

## README: overshoot

I used a feedforward PI controller to produce this trajectory. I chose  $K_p = 5$  and  $K_i = 50$ .

The initial gripper-less configuration is

$[\pi/6, 0, 0.2, 0, \pi/3, -\pi/4, -\pi/2, 0, 0, 0, 0, 0]$