

## [PRACTICAL] Recorded Session

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### Recorded Session on FAQs

This is the **3rd post** in **[PRACTICAL]** series in Stage-2 of our theme.

We collected some common important questions, mistakes and learnings from our previous experiences dealing with control system based themes and robots.

We kept on adding few more good resources as we observed and collected newer questions and issues from the open door sessions - thanks to your participation and active involvement. These included some material and videos referred from the internet as well.

But for few very important - implementation specific topics, it wasn't easy to give you a ready reference. OR at least not something easy to read/watch and understand.

#### ***So we decided to create something ourselves...***

Following are few timestamps of the video we created,

**00:00** - Intro to TWO self balancing systems

**02:55** - Yaw feedback from IMU and effect of mounting

**08:19** - Discrete vs Continuous : Uniform & Non-uniform sampling

**24:11** - Observing Derivative gain

**36:45** - Cascade(Series) PID Intuition

**57:11** - Integral Windup problem and Solutions

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