

Progress report 3

Summary

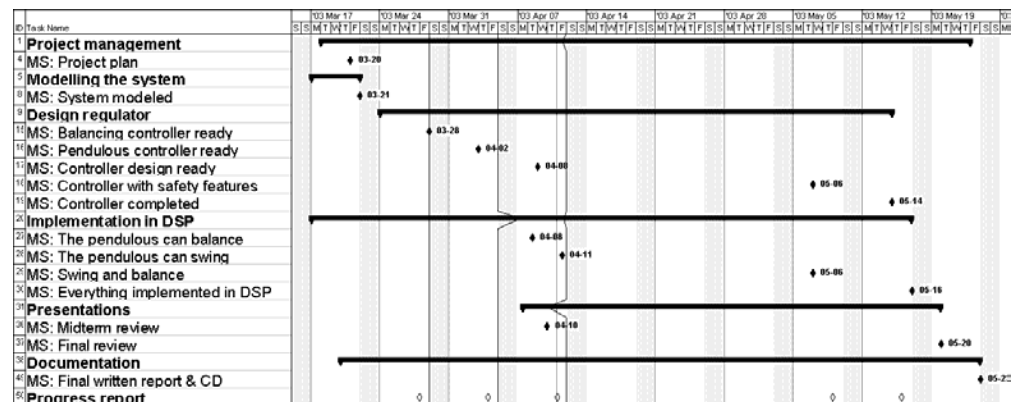
Events since previous report

- Milestone passed: Controller design ready.
- Milestone passed: Midterm review.
- We have a working PID-controller.

What happens next

- Better Anti-windup in the PID-controller.
- Investigate more advanced derivation algorithms.
- Better integration between different controllers.
- Try different controller for the swing.

Current time scale



Obstacles and possibilities

We think the problem with our PID is caused by Integral wind-up. The controller works quite good but with better anti wind-up, we think it will work better.

Other

We are now working with another controller for the swing, that will hopefully give us more control of that part, so that the pendulum never misses balance state. We will also clean up the implementation code and write the different controllers in sub functions. This makes it easier to switch between the controllers.