Last week the group wasn’t able to meet due to holidays and re exams. This week we’ve managed to balance a few seconds more than our last best try, still with a PID controller. A problem is that we get quite different results from time to time when we run. This might be due to battery level or different light conditions (though our sensor is said to be able to handle that). We will try to fix this by taking battery level into account in the controller.

Our robot used to turn because the motors rotate at different speeds. We improved this by implementing an experimental formula. The robot still turns a bit, though much less.

Our LQ controller is behaving sort of correctly though it’s very unable to balance. We are trying to find a better L for feedback.

Finally we are trying to verify our model with the greybox tool in matlab. We’re not able to make the tool behave in a satisfying way.