Hello!

This week we gotten our robot to balance really well. The reason is that we found a few errors in the model. With this new model we can balance our robot indefinately. During our long runs we noticed that the robot started turning (either left of right). As far as we can see its due to some commands not getting executed by the motors. To counter this effect we added a simple P-regulation which keep the robot steady. An added bonus of this is that we now can make it turn at will. Previously we were only concerned about balancing the robot.

An other annoyance is that the conditon of the batteris are not that great. We only get 10 minutes runtime on a full charge. Previously we' ve gotten about an hour on a full charge.

cheers
Group 5