Dgs Ramsete Iii V9 05 5 [NEW]

If the gains are in FULL RAMSETE mode, and the agent has a new state Y + d, then the controller must update the velocities that are in the vx, vy, and omega elements of the ChassisSpeeds vector. This is calculated as follows: The robot encodes its position and orientation in a quaternion. The final steps are to rotate the resulting quaternion into a euler angle vector and convert that to the angle format used by RAMSETE. This is to ensure RAMSETE is not confused by the 90 degree rolls that occur when converting between rotations and angles. It must be noted that the initial position and heading for the robot before calibrations is used by RAMSETE. This was always known and results in RAMSETE converging very quickly. Therefore the robot always starts at the same initial pose. With a value of mode of 2, the standard controller given by RAMSETE has an additional component that attempts to reduce the error in the velocity by a factor of (1 + 5 ⬜ot loss / gain), where loss is the sum of the absolute value of all quaternion-relative errors and the gain is a factor between the loss and the error in all velocity components. This loss value is reduced by a factor of (1 + 5 ⬜ot loss / gain) as the desired angle error (in degrees) increases. However, one must note that this is always performed after all other state adjustments. This means that this gain adjustment is being carried out after the robot is at least partially in a desired state and most likely looking at a goal.

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