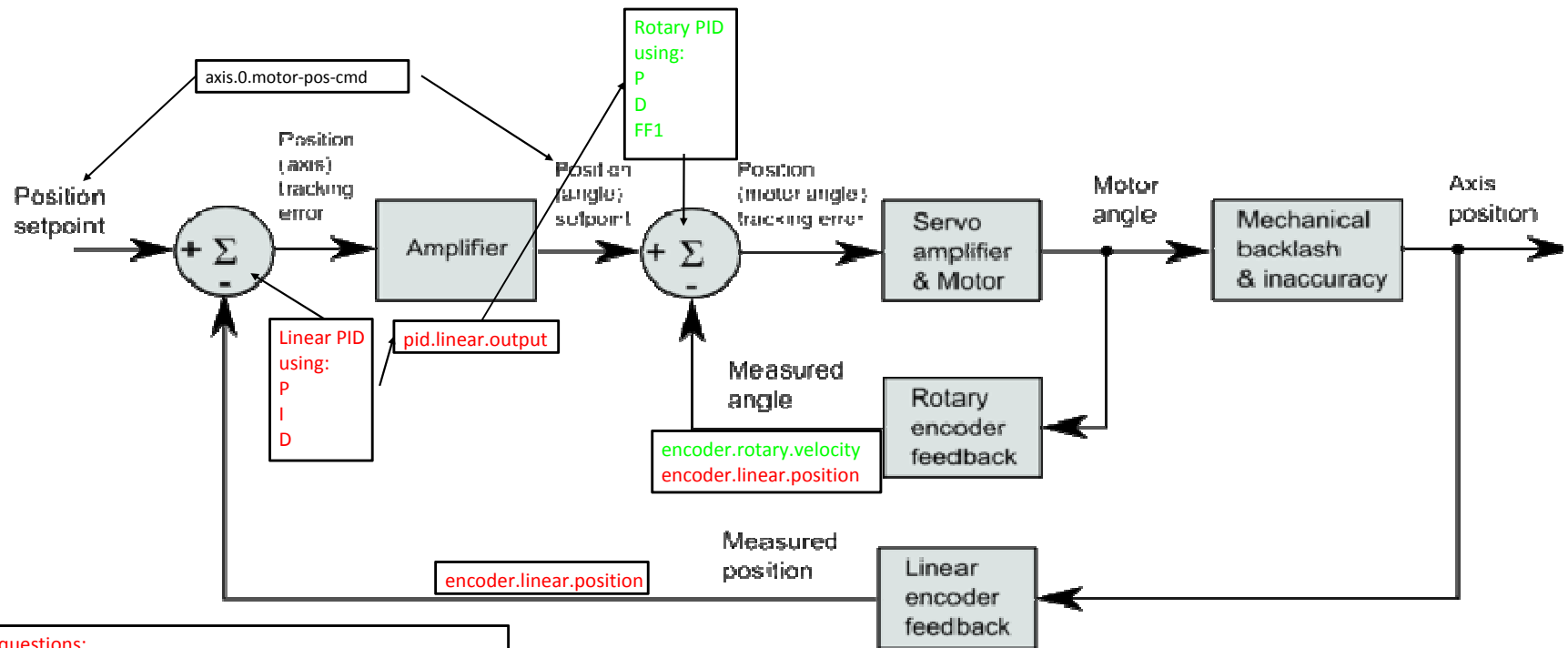




Three questions:

1. Is the block diagram as laid out above viable?
2. Would need to set Linear and Rotary P and D terms to levels where they would be complementary, not fighting. If positional feedback to both PID's is from the linear encoder, may this be possible? OR
3. Is it possible to simply have ONLY velocity (no positional) feedback into the rotary PID and then use the pid.linear.output to feed into the pid.rotary.command pin to have the rotary PID only working using velocity info (but this seems to be a mix of position/velocity units...)