

Progetto Regolatore PD

$$PD(s) = K_p + \frac{K_d \cdot s}{1 + \frac{K_d \cdot s}{N}}$$

$$\begin{cases} K_p = 0.8 \cdot K_c \\ K_d = K_p \cdot P_c / 8 \end{cases}$$

$$1 + \frac{K_d \cdot s}{N}$$

PID

$$\begin{cases} K_p = 0.6 \cdot K_c \\ K_i = 2 K_p / P_c \\ K_d = K_p \cdot P_c / 8 \end{cases}$$

$$G(s) = \frac{1}{s(s+5)^2}$$

Sistema di "tipo 1"

$$PID(s) = K_p + \cancel{K_i \frac{1}{s}} + \frac{K_d \cdot s}{1 + \frac{K_d \cdot s}{N}} \equiv PD(s)$$