

# Progetto Regolatore PD

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

$$\left\{ \begin{array}{l} K_p = 0.8 \cdot K_c \\ K_d = K_p \cdot P_c / 8 \end{array} \right.$$

$$\left\{ \begin{array}{l} K_p = 0.6 \cdot K_c \\ K_i = 2 K_p / P_c \\ K_d = K_p \cdot P_c / 8 \end{array} \right.$$

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

PID

$$\left\{ \begin{array}{l} K_p = 0.6 \cdot K_c \\ K_i = 2 K_p / P_c \\ K_d = K_p \cdot P_c / 8 \end{array} \right.$$

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

Sistema di  
"tipo 1"

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