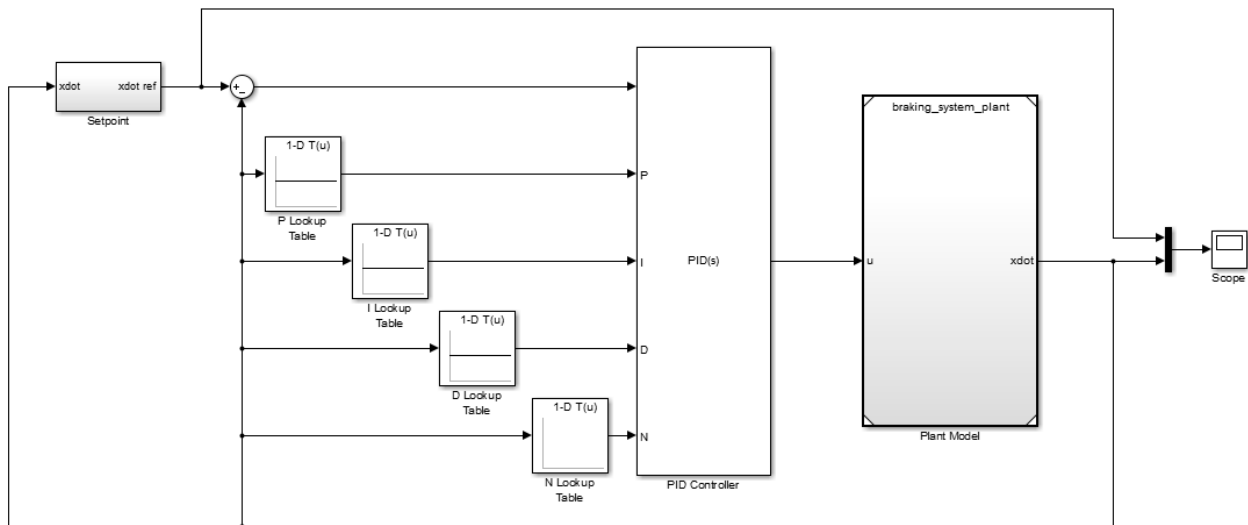
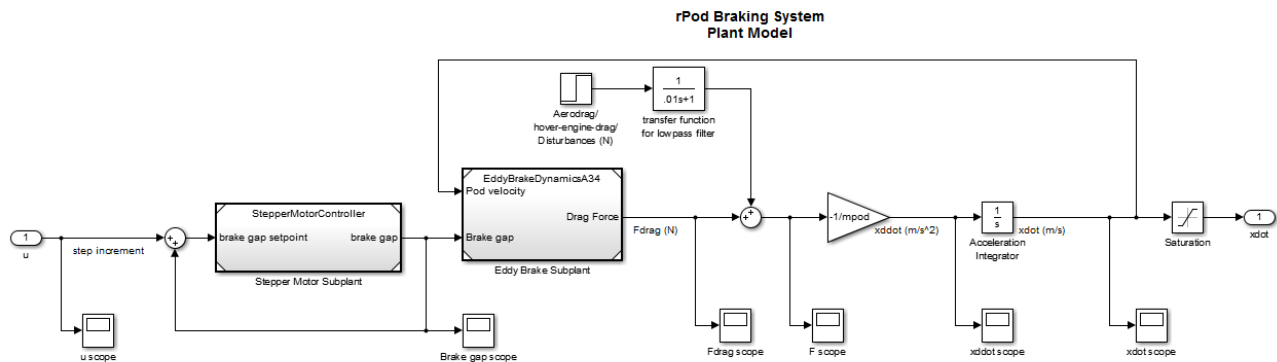
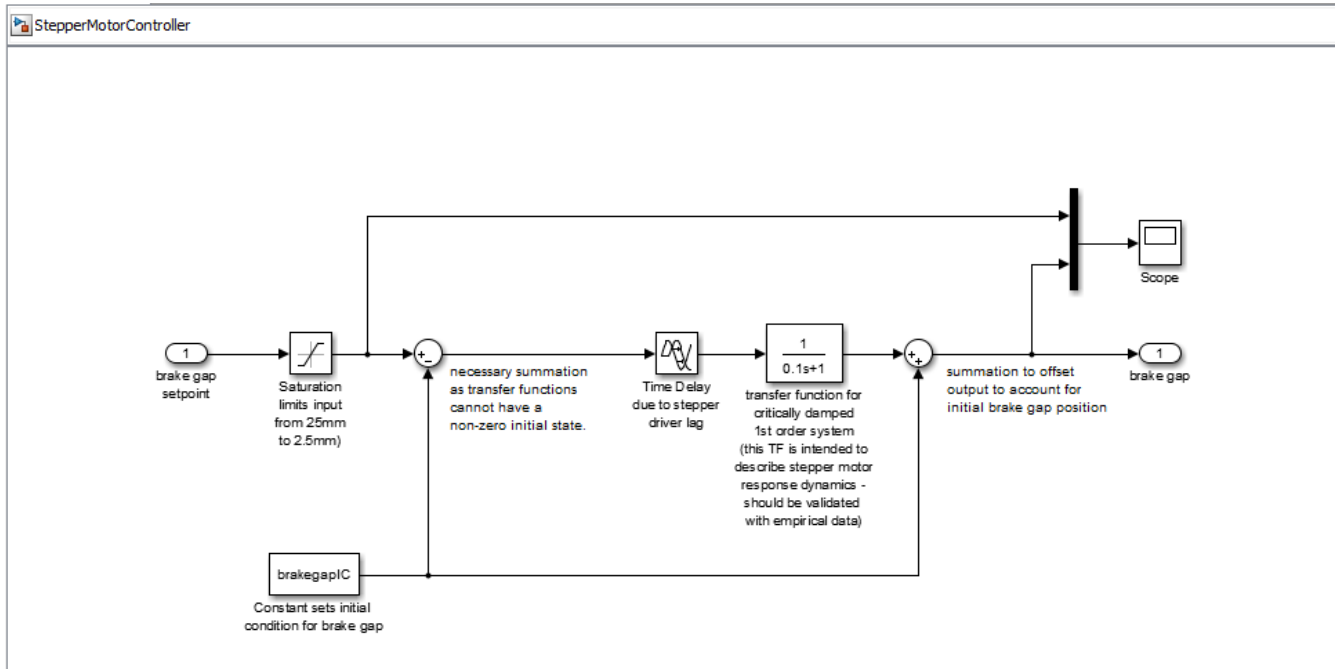


# **rPod Braking System with Gain-Scheduled PID Control**



BrakingSystemPlant ▶





$$K_p + K_i * \frac{1}{s} + K_d * \frac{s}{T_f * s + 1}$$

with  $K_p = 0.378$ ,  $K_i = 0.17$ ,  $K_d = 0.206$ ,  $T_f = 0.0183$

^All break points generated from PID tuner came out to have the same gains. May change once stepper motor block gets updated.