Tabela de Zieger-Nichols

Tipo de controle	K_p	T_i	T_d	K_i	K_d
P	$0,50K_u$	–	–	–	–
PI	$0,45K_u$	$0,83T_u$	–	$0,54(K_u/T_u)$	–
PD	$0,80K_u$	–	$0,125T_u$	–	$0,100K_uT_u$
PID Clássico	$0,60K_u$	$0,50T_u$	$0,125T_u$	$1,20(K_u/T_u)$	$0,075K_uT_u$
Integrador de Pessen	$0,70K_u$	$0,40T_u$	$0,150T_u$	$1,75(K_u/T_u)$	$0,105K_uT_u$
Com overshoot	$0,3\dot{3}K_u$	$0,50T_u$	$0,33\dot{3}T_u$	$0,66(K_u/T_u)$	$0,11\dot{1}K_uT_u$
Sem overshoot	$0,20K_u$	$0,50T_u$	$0,33\dot{3}T_u$	$0,40(K_u/T_u)$	$0,066K_uT_u$