

Controller	v_r (ms ⁻¹)	k_p	k_i	k_d	θ (rad)
PID	0.001	1	1	1	1
PID	0.01	1	1	1	1
PID	0.1	1	1	1	1
PID	1	1	1	1	1
PID	10 (slow – 22 mph)	1	1	1	1 (not yet realistic)
PID	100 (fast – 223 mph)	1	1	1	1 (not yet realistic)
PID	26.822 (60 mph)	10	1	1	0.261 (15°)
PID	26.822 (60 mph)	100	1	1	0.261 (15°)
PID	26.822 (60 mph)	0.001	1	1	0.261 (15°)
PID	26.822 (60 mph)	0.001	10	1	0.261 (15°)
PID	26.822 (60 mph)	0.001	10	0.1	0.261 (15°)
PID	26.822 (60 mph)	?	?	?	0.261 (15°)
PID	31.292 (70 mph)	??	??	??	0.349 (20°)