

1. What gain parameters did you end up using for your PI controller?
 - a. Describe the response of the system to speed changes.

I found that using a K_i and K_p of 1 worked the best and got results incredibly quickly and accurately. As I raised K_p it worked the same way raising speed but undershot and struggled with lowering speed. Raising K_i created an issue of overshooting for both raising and lowering speeds. I did notice that no matter what I set the K_i and K_p to the motor could only reach 95 rpm even though theoretically it should be able to reach higher the motor would stop at 95.