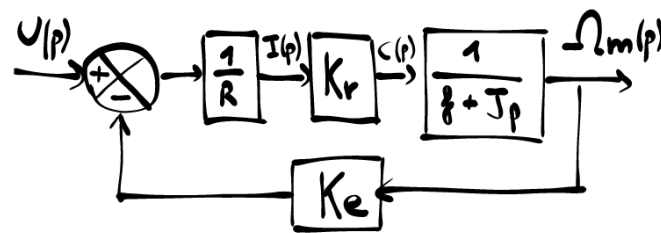
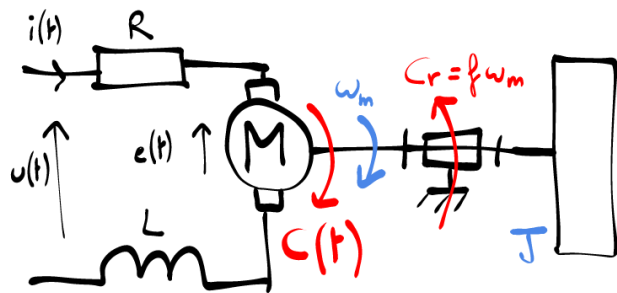
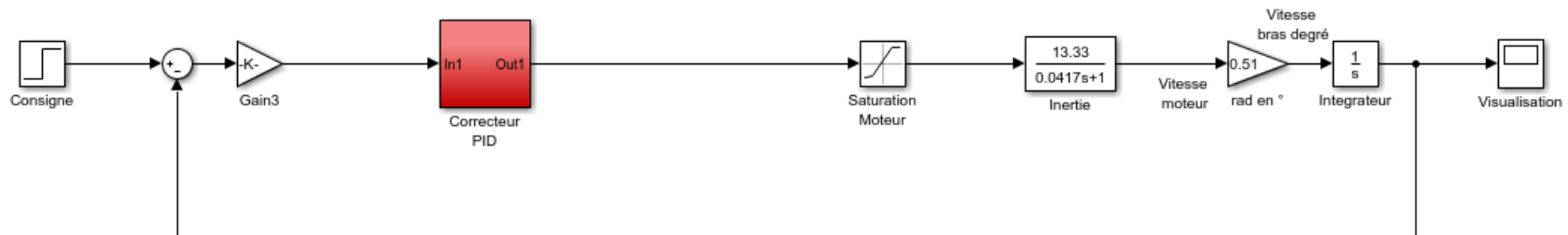


MAXPID

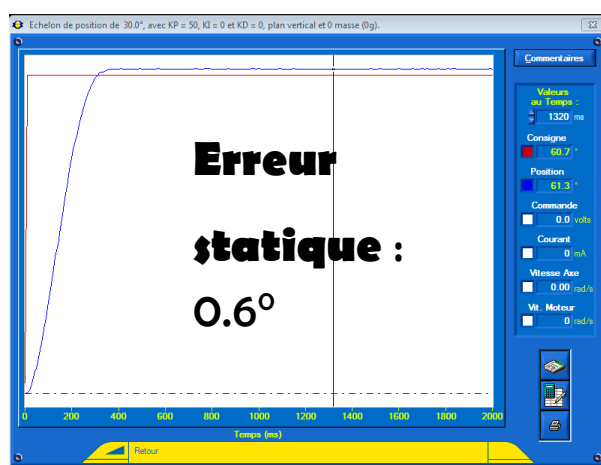
Correction des systèmes asservis



Moteur approximé à un système de 1er ordre

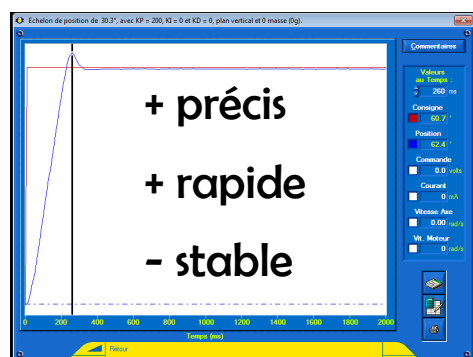
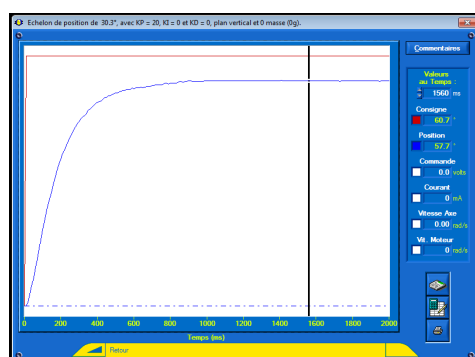


EXPERIMENTAL



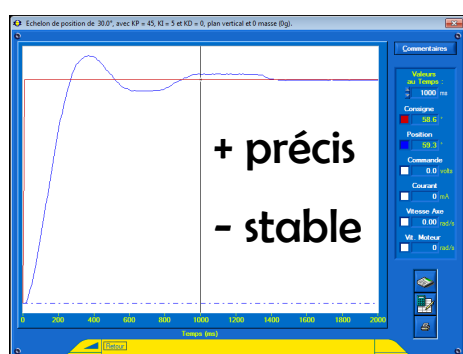
Erreur statique : 0.6°

Il faut ajouter un **intégrateur** dans le correcteur (en amont de la perturbation).

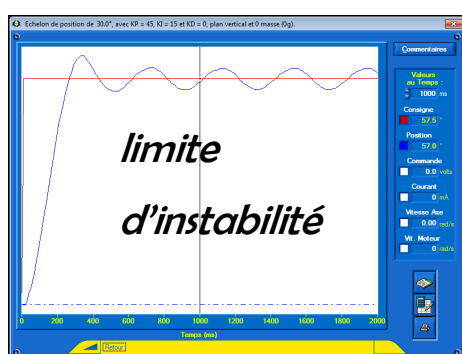


**+ précis
+ rapide
- stable**

Influence du **gain Kp**

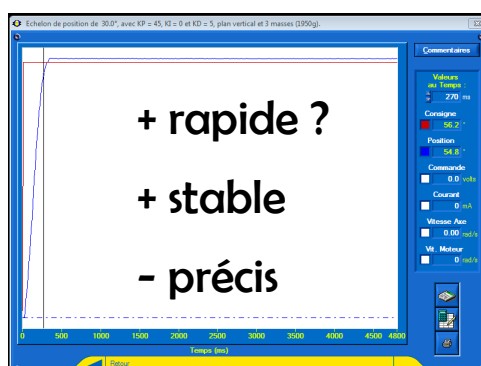


**+ précis
- stable**



limite d'instabilité

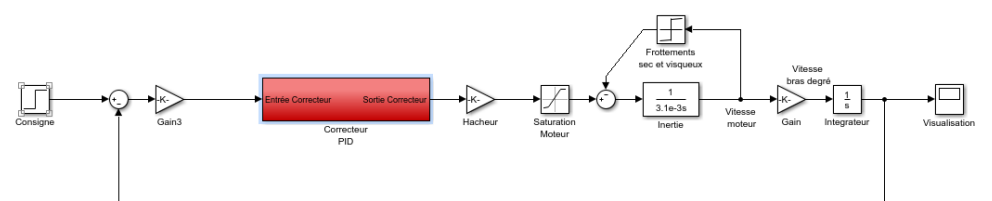
Influence de **Ki**



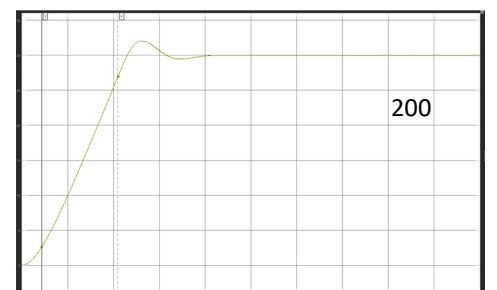
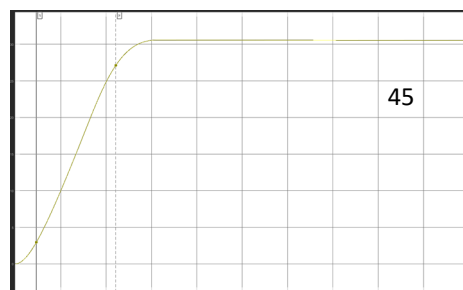
**+ rapide ?
+ stable
- précis**

Influence de **Kd**

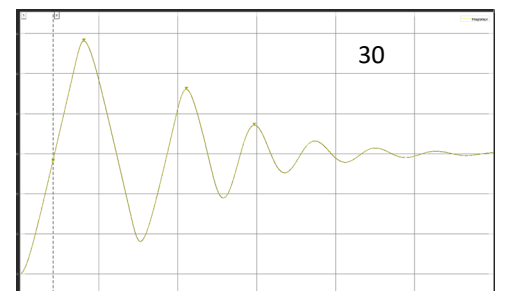
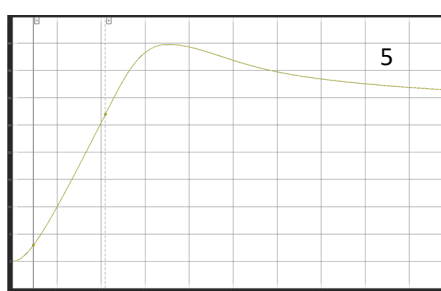
MODELISATION



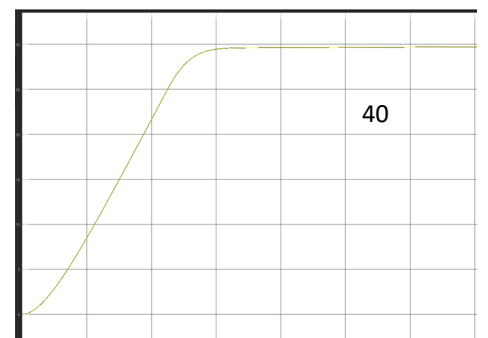
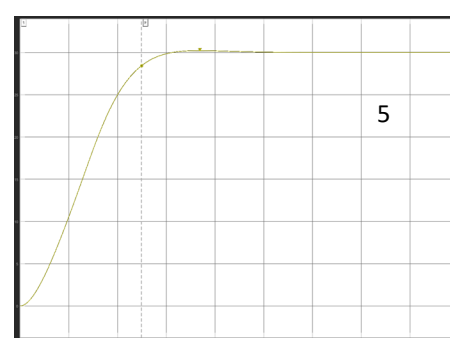
- Impact de la saturation :
- Ajout des frottements visqueux :



Influence du **gain Kp**



Influence de **Ki**



Influence de **Kd**