

A3 PID Controller
Pushpa Koirala = Ag1715

P controller
 $con = K_p \times e$
 $K_p = \text{constant}$
 $e = Sp - Me$

PI Controller
 $con = K_p \times e + 1/s$

PI Controller
 $con = K_p \times e + 1/s \times e + du/ds$

