.ac list {w/(2*pi)} .include control_theory1.lib .step dec param w 1m 1k 100 .tran 1 U1 U2 U3 -in ap1 in 0 tt1 in ap2 in **V1** TT AP1 AP2 Kp=.8 Tt=.2 KP=2 T=.1 KP=2 D=1 w0=10 PWL(0 0 1m 10) AC₁ U4 U5 U6 d 0 dt1 in inin pd DT1 PD D Kp=1 Tv=.01 Kd=1m Kd=0.1 T1=0.1 **U8 U7** 0 0 −i -it1 in in IT1 Ki=1 Ti=1 KP=2 Ti=.1 T1=1 U9 **U10 U11** 0 in 0 p in⊣ 11 0 **p2** р3 ıξ 髙 Ρ **P2 P**3 Kp=0.5 Kp1=1 Kp2=1 Kp1=1 Kp2=1 Kp3=1 **U12 U13 U14** 0 pid in 0 рi in in 0 pidt1 PID PIDT1 PI Kr=1 Tn=1 Kr=0.5 Tn=1 Tv=1m Kr=0.1 Tn=.2 Tv=1 T1=0.1 **U15 U16** pdt1 in 0 in ppt1 PDT1 PPT1 Kp=.5 Tv=.2 T1=.1 Kp=1 Tv=0.2 T1=0.5 **U17 U18 U19** in 0 pt1 0 pt2 in 0 pt2s in PT1 PT2 PT2S Kp=2 T1=.1 Kp=2 T1=.1 T2=.1 Kp=2 D=0.5 w0=10