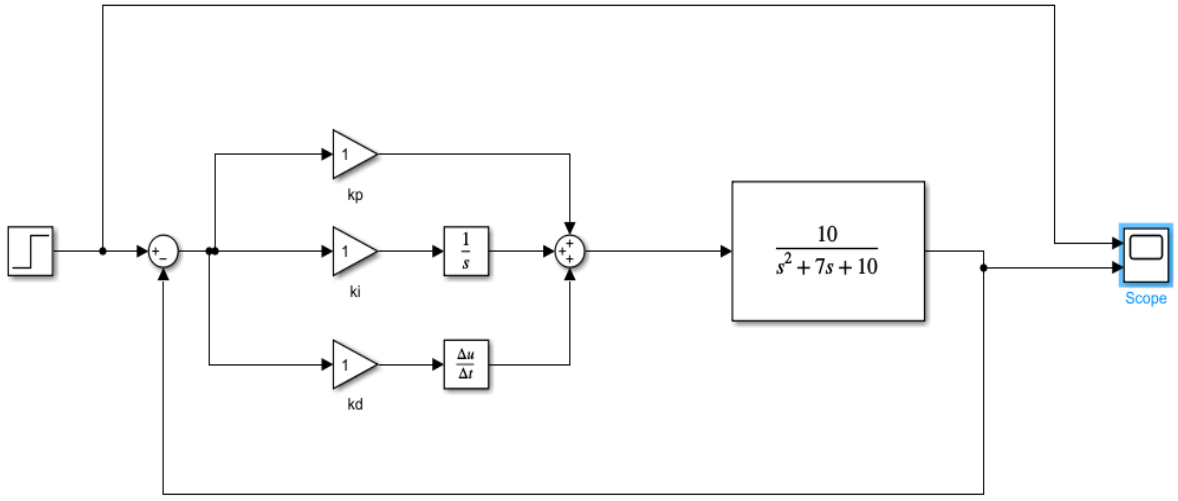
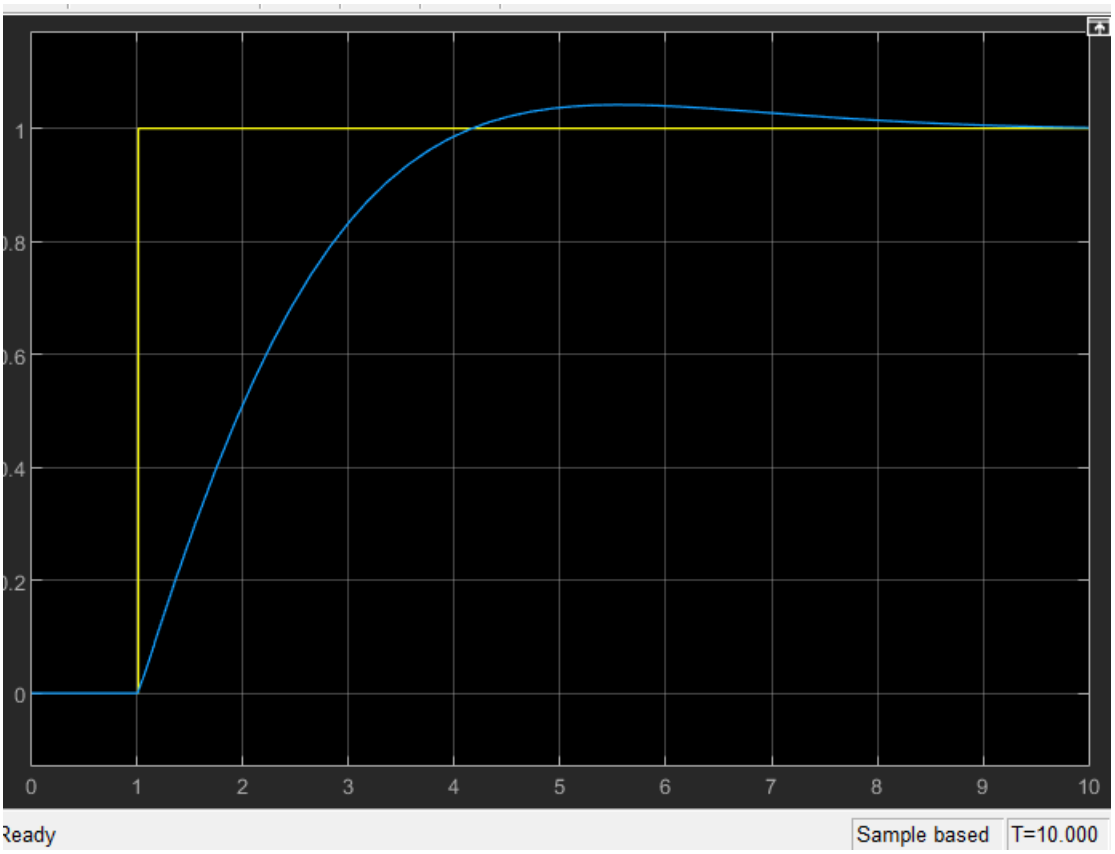
Mazen HossamEldeen Hassan MBD-Diploma

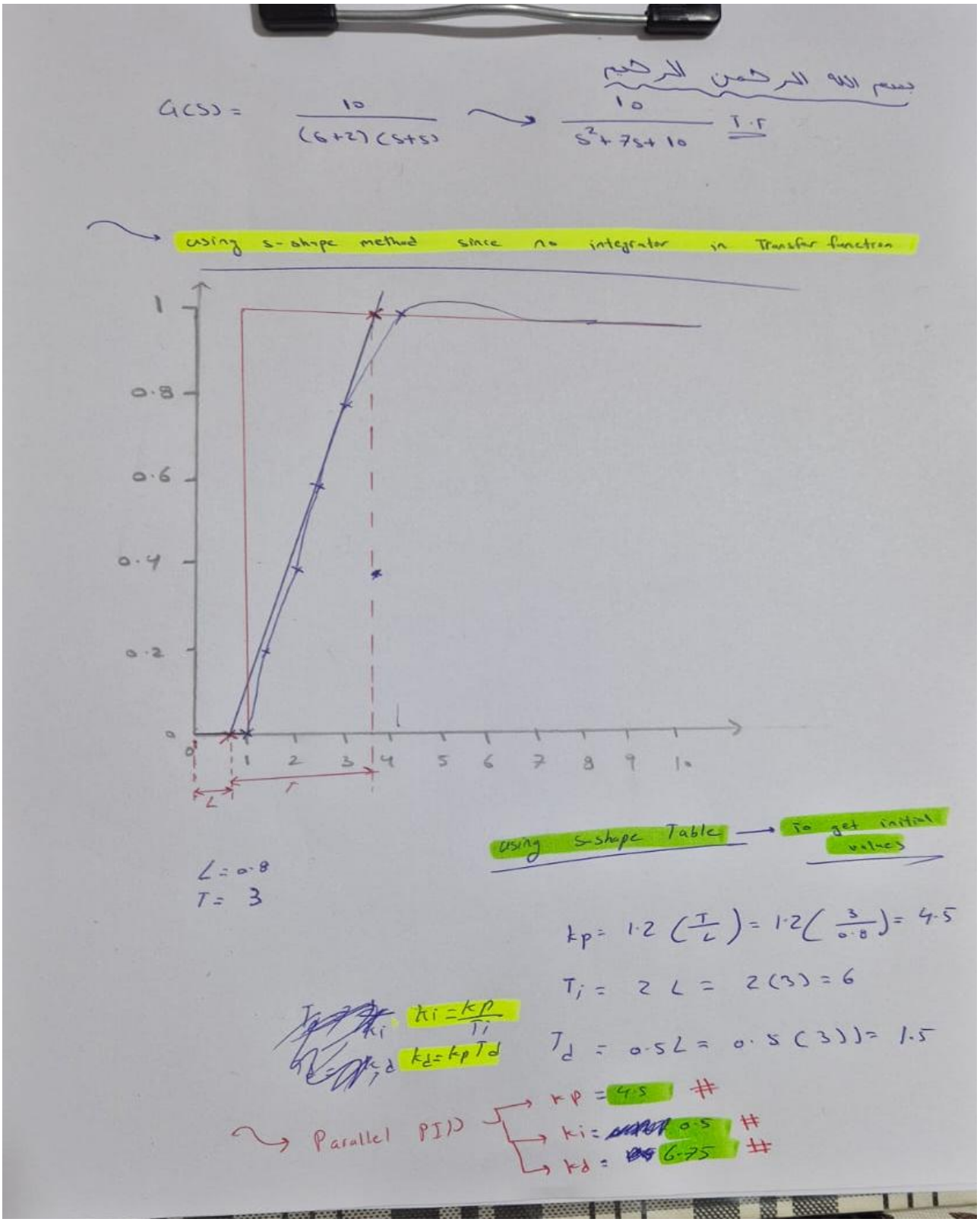
PID controller tunning using s shape methods

→Intitial PID Paramters





→S-shape method



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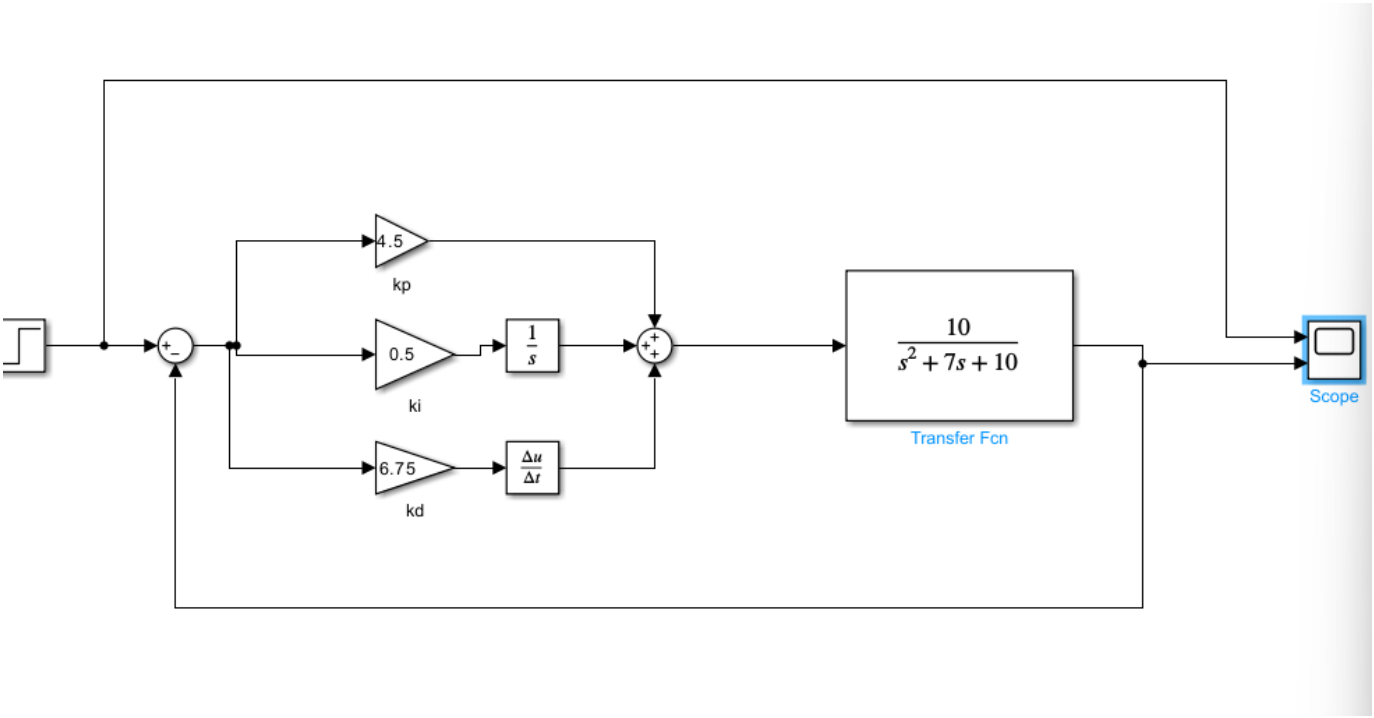
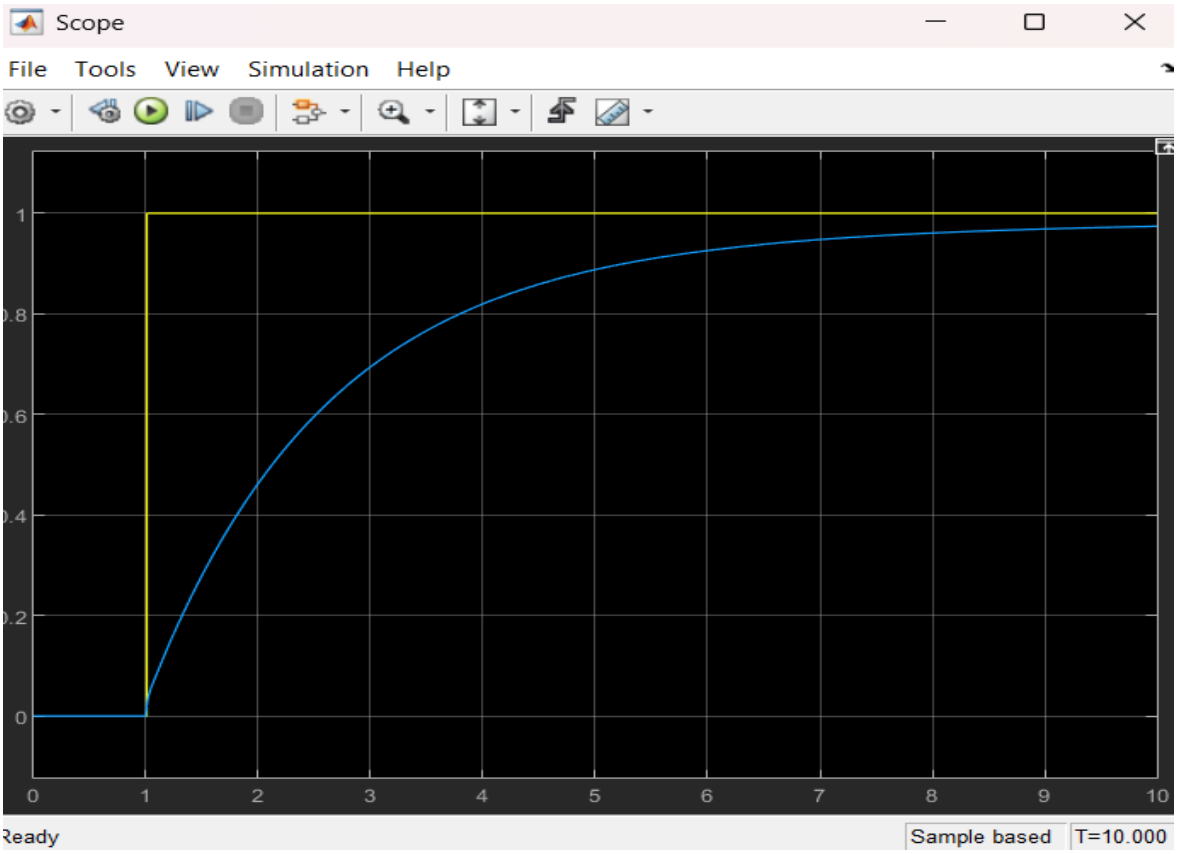
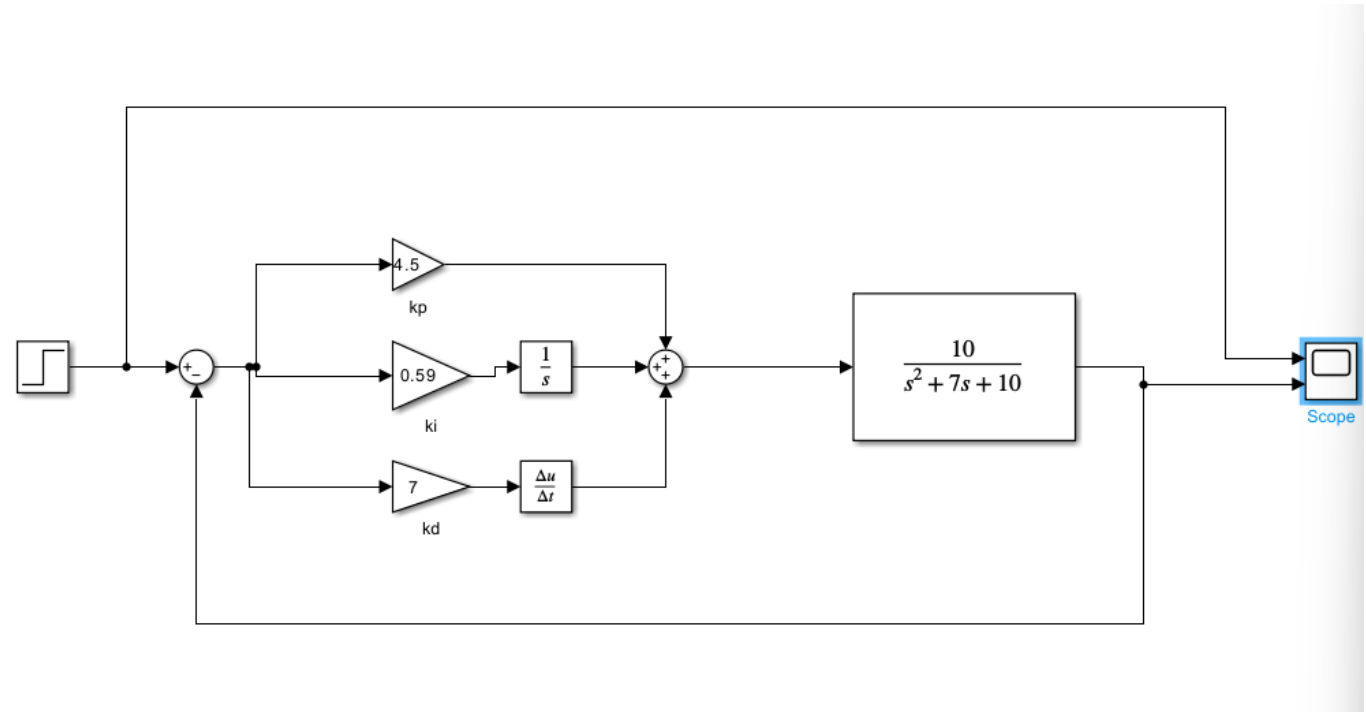
->Using values obtained from s-shape Kp=4.5 , ki = 0.5, kd =6.75

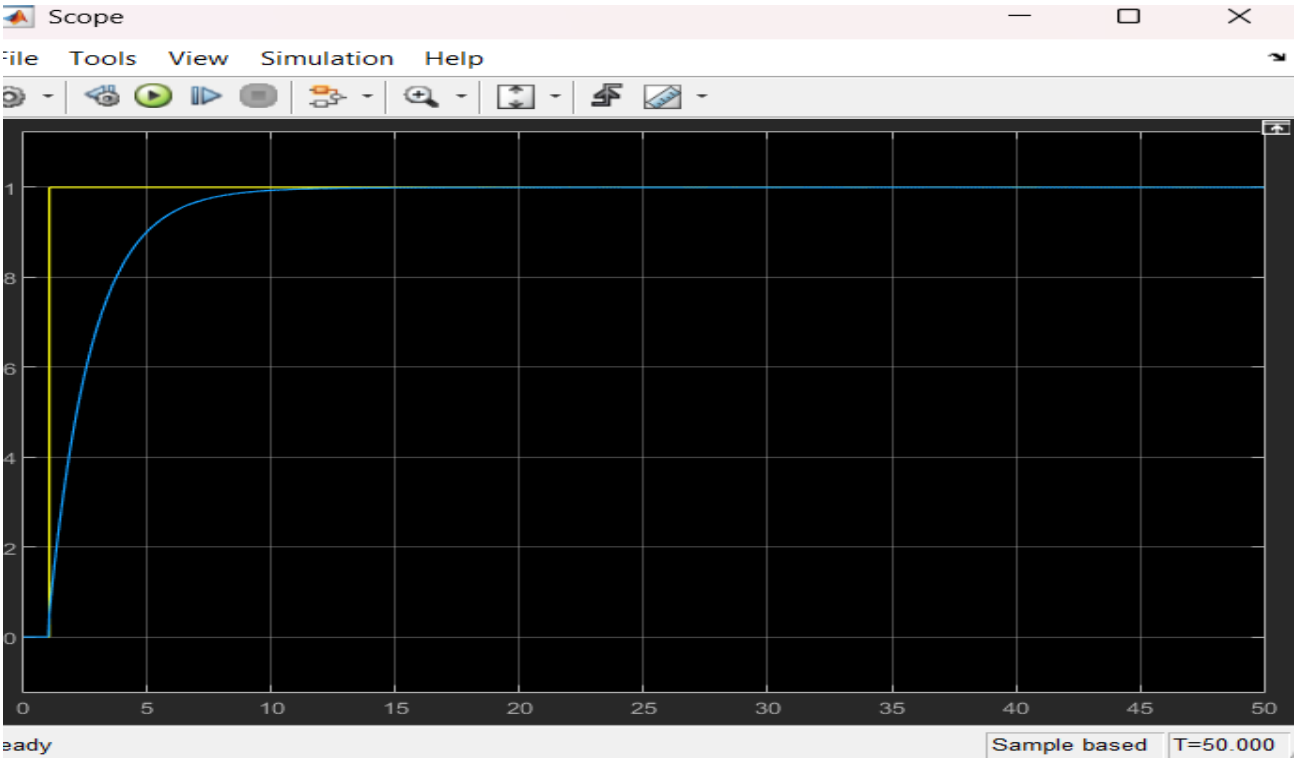




-After inserting these value we can see the overshoot of the system has decreased and system is close to steady state error equal to zero.

->Increasing slightly ki to 0.59 and kd to 7





->After increasing these values slightly the system was able to reach steady state error to zero and no overshoot.