

1. What gain parameters did you end up using for your PI controller?

- The gain parameters I used was 3 for K_i and 3 for K_p .
- Using these parameters, I was able to get an accurate climb to the target RPM.

There was a bit of overshooting but it stabilized fast. When going to a target RPM that is smaller than the initial speed, there was also some undershooting but it stabilized to the target RPM very fast. Below are the results in a line graph.



