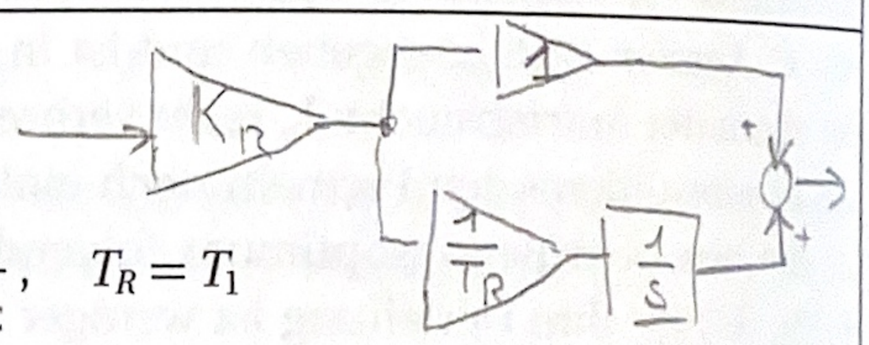
Strecke $F_o(s)$	Regler $G_K(s)$	Einstellregeln
$\frac{1}{a_0+a_1s+a_2s^2+\ldots}$	PI $\frac{r_0+r_1s}{2s}$	$r_0=a_0\frac{a_1^2-a_0a_2}{a_1a_2-a_0a_3}$, $r_1=a_1\frac{a_1^2-a_0a_2}{a_1a_2-a_0a_3}-a_0$
$\frac{1}{a_0+a_1s+a_2s^2+\ldots}$	PID $\frac{r_0+r_1s+r_2s^2}{2s}$	$r_0=\frac{1}{D}\begin{vmatrix} a_0^2 & -a_0 & 0 \\ -a_1^2+2a_0a_2 & -a_2 & a_1 \\ a_2^2+2a_0a_4-2a_1a_3 & -a_4 & a_3 \end{vmatrix}$ $r_1=\frac{1}{D}\begin{vmatrix} a_1 & a_0^2 & 0 \\ a_3 & -a_1^2+2a_0a_2 & a_1 \\ a_5 & a_2^2+2a_0a_4-2a_1a_3 & a_3 \end{vmatrix}$ $r_2=\frac{1}{D}\begin{vmatrix} a_1 & -a_0 & a_0^2 \\ a_3 & -a_2 & -a_1^2+2a_0a_2 \\ a_5 & -a_4 & a_2^2+2a_0a_4-2a_1a_3 \end{vmatrix}$ $D=\begin{vmatrix} a_1 & -a_0 & 0 \\ a_3 & -a_2 & a_1 \\ a_5 & -a_4 & a_3 \end{vmatrix}$
$\frac{K_S}{\prod_{\nu=1}^{n}(1+T_\nu s)}$ $T_1 >> T_\Sigma=\sum_{\nu=2}^{n}T_\nu$	PI $K_R\frac{1+T_Rs}{s}$	$K_R=\frac{1}{2K_ST_\Sigma}$, $T_R=T_1$ 
$\frac{K_S}{\prod_{\nu=1}^{n}(1+T_\nu s)}$ $T_1, T_2 >> T_\Sigma=\sum_{\nu=3}^{n}T_\nu$ 2 große Zeitkonstanten	PI $K_R\frac{1+T_Rs}{s}$	$K_R=\frac{1}{2K_S}\quad\frac{T_1^2+T_1T_2+T_2^2}{(T_1+T_2)T_1T_2}$ $T_R=\frac{(T_1^2+T_2^2)(T_1+T_2)}{T_1^2+T_1T_2+T_2^2}$
	PID $K_R\frac{(1+T_{R1}s)(1+T_{R2}s)}{s}$	$K_R=\frac{1}{2K_ST_\Sigma}$, $T_{R1}=T_1$, $T_{R2}=T_2$

Tabelle 6-3: Einstellregeln zum Betragsoptimum