

* Pengendali PID

P = Proportional
I = Integral
D = Differential

$$H(s) = K_p + \frac{K_I}{s} + K_D s$$

* $K_p = 0 \rightarrow PI \rightarrow H(s) = \frac{K_I s + K_I}{s}$ order pertama
 $p = 0$
 $z = -\frac{K_I}{K_p}$

* $K_I = 0 \rightarrow PD \rightarrow H(s) = K_p + K_D s$ $\rightarrow m > n$

(tidak dapat direalisasi sendiri)

* $K_D = K_I = 0 \rightarrow P \rightarrow H(s) = K_p$ order nol

* $\{K_p, K_I, K_D\} \neq 0 \rightarrow PID \rightarrow H(s) = \frac{K_p s + K_I + K_D s^2}{s}$

Order Pertama: $m > n \rightarrow$ 2 zero
1 pole

$G(s)$ minimal: $G(s) = \frac{1}{s}$