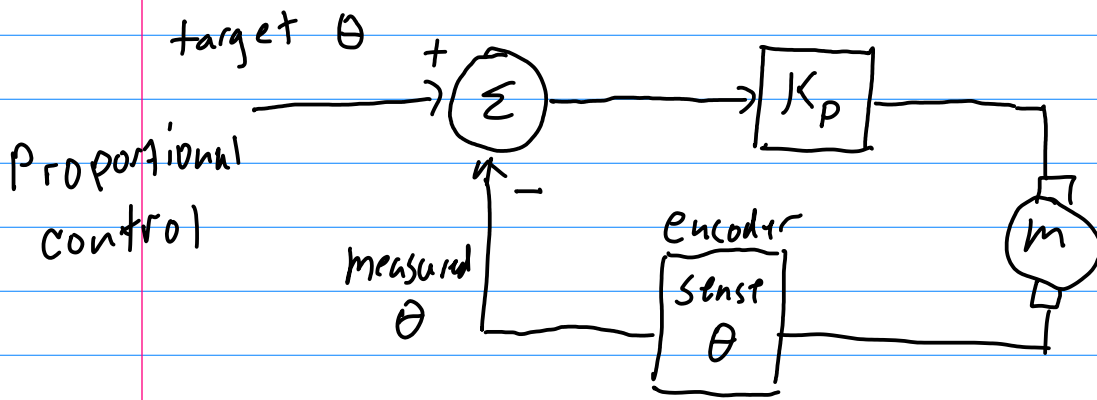
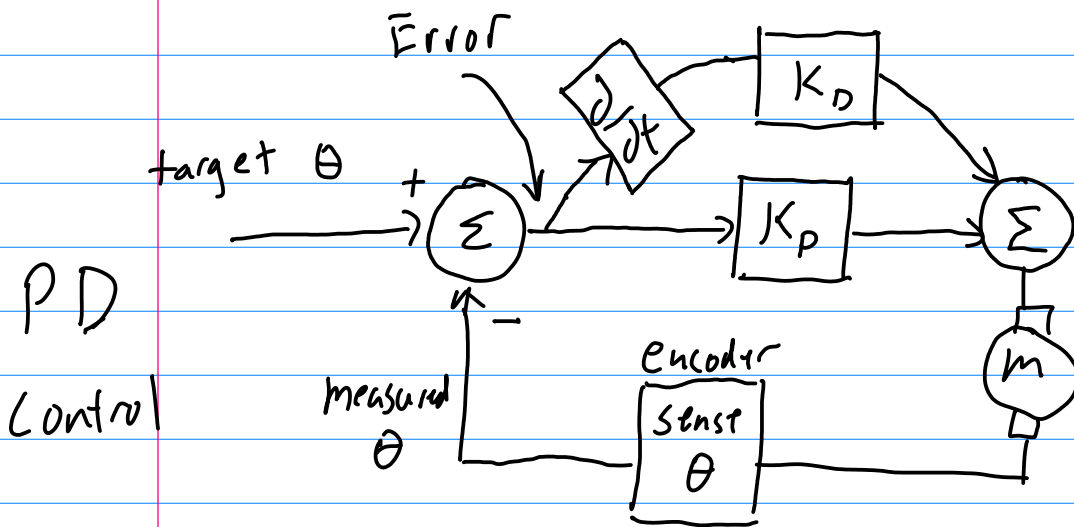


PID - proportional, integral, differential



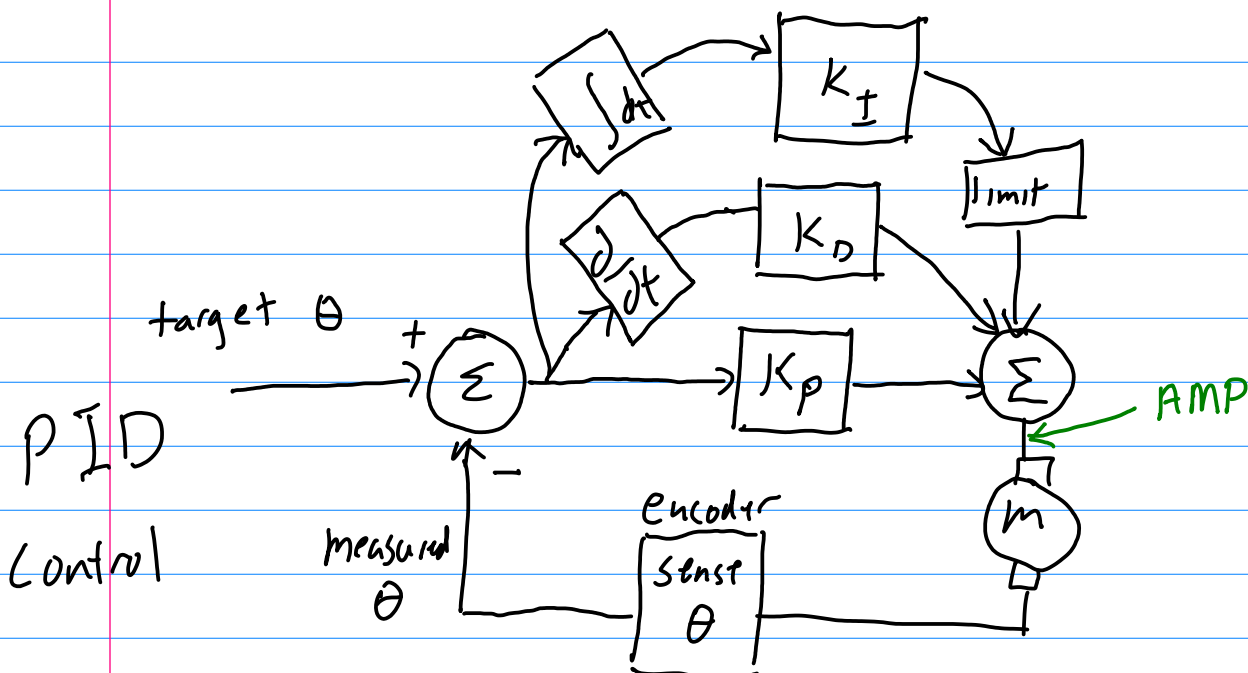
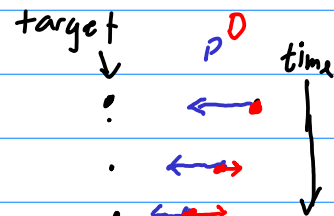
K_p = proportional gain

Suffer from oscillations



K_p = proportional gain

K_d = Differential gain



K_i pull into final position