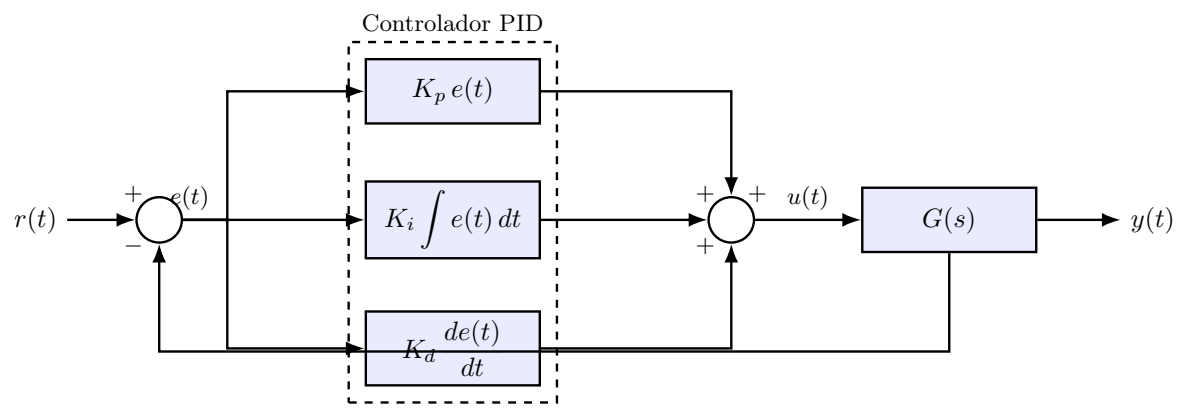
Controlador PID
$K_p\, e(t)$
$K_i \int e(t)\, dt$
$K_d \dfrac{de(t)}{dt}$
$r(t)$
$e(t)$
$u(t)$
$G(s)$
$y(t)$