PID trim gain fact
0.00 ... 100.00
P2256 (100.00)

CI:PID trim source
P2254
(0:0)

CI: PID setpoint
P2253
(0:0)

PID setp.gain fact
0.00 ... 100.00
P2255 (100.00)

PID setp. ramp-up
0.00 ... 650.00 [s]
P2257 (1.00)

PID setp. ramp-dwn
0.00 ... 650.00 [s]
P2258 (1.00)

PID setp.filt.Tcon
0.00 ... 60.00 [s]
P2261 (0.00)

CO: Filt. PID setp
r2262

CO: PID setp <-RFG
r2260

PID prop. gain
0.000 ... 65.000
P2280 (3.000)

PID integral time
0.000 ... 60.000 [s]
P2285 (0.000)

Kp     Tn

CO: PID error
r2273

CO/BO: Act StatWd2
r0053
r0053.11
r0053.10

r2294
CO: Act.PID output

Fdbck.filt. Tconst
0.00 ... 60.00 [s]
P2265 (0.00)

CI: PID feedback
P2264
(755:0)

r2266
CO: PID filt.fdbck [%]

PID fdbck max. val
-200.00 ... 200.00 [%]
P2267 (100.00)

PID fdbck min. val
-200.00 ... 200.00 [%]
P2268 (0.00)

PID feedback gain
0.00 ... 500.00
P2269 (100.00)

PID trans. type
0 ... 1
P2271 (0)

PID fdbck fnct sel
0 ... 3
P2270 (0)

r2272
CO: PID scal fdbck [%]

PID outp.upper lim
-200.00 ... 200.00 [%]
P2291 (100.00)

PID lim. ramp time
0.00 ... 100.00 [s]
P2293 (1.00)

PID outp.lower lim
-200.00 ... 200.00 [%]
P2292 (0.00)

P2200 = BI: Enable PID controller

| 1 | 2 | 3 | 4 | 5 | 6 | 7 | 8 |
|---|---|---|---|---|---|---|---|

| Setpoint Channel | | | | | 5100_PID.vsd | Function diagram | - 5100 - |
| PID controller | | | | | 01.07.2002   V1.1 | MICROMASTER 411 | |