Modulus optimum method

Controlled system $F_O(s)$	Controller $G_K(s)$	Settings
$\dfrac{K_S}{\prod_{\nu=1}^{n}(1+T_\nu s)}$ 1 big (dominant) time constant $T_1 >> T_\Sigma = \sum_{\nu=2}^{n} T_\nu$	PI $K_R \dfrac{1+T_R s}{s}$	$K_R = \dfrac{1}{2K_S T_\Sigma}$ $T_R = T_1$ (compensation of dominant time constant)
$\dfrac{K_S}{\prod_{\nu=1}^{n}(1+T_\nu s)}$ 2 big (dominant) time constants $T_1, T_2 >> T_\Sigma = \sum_{\nu=3}^{n} T_\nu$	PI $K_R \dfrac{1+T_R s}{s}$	$K_R = \dfrac{1}{2K_S} \cdot \dfrac{T_1^2 + T_1 T_2 + T_2^2}{(T_1 + T_2) T_1 T_2}$ $T_R = \dfrac{(T_1^2 + T_2^2)(T_1 + T_2)}{T_1^2 + T_1 T_2 + T_2^2}$
	PID $K_R \dfrac{(1+T_{R1} s)(1+T_{R2} s)}{s}$	$K_R = \dfrac{1}{2K_S T_\Sigma}$ $T_{R1} = T_1$ $T_{R2} = T_2$ (compensation of dominant time constants)

More info can be found e.g. here:
http://www.eal.ei.tum.de/lehre/bdgea/Regelungsskript_eng.pdf