P-T1-Strecke

Regler	F_O und Kennwerte	F_W und Kennwerte	F_{Zv} und Kennwerte	e_{bw}	e_{bZv}	e_b
P	**P-T1-Verhalten** $K_{Pg} = K_{PS} \bullet K_{PR}$ $T_{1g} = T_1$	**P-T1-Verhalten** $K_{Pg} = \frac{K_{PS} \bullet K_{PR}}{1+(K_{PS} \bullet K_{PR})}$ $T_{1g} = \frac{T_1}{1+(K_{PS} \bullet K_{PR})}$	**P-T1-Verhalten** $K_{Pg} = \frac{K_{PS}}{1+(K_{PS} \bullet K_{PR})}$ $T_{1g} = \frac{T_1}{1+(K_{PS} \bullet K_{PR})}$	$e_{bw} = \frac{W}{1+K_{PS} \bullet K_{PR}}$	$e_{bZv} = \frac{K_{PS} \bullet Z_V}{1+K_{PS} \bullet K_{PR}}$	$e_b = \frac{W-(K_{PS} \bullet Z_V)}{1+K_{PS} \bullet K_{PR}}$
I	**I-T1-Verhalten** $K_{Ig} = K_{PS} \bullet K_{IR}$ $K_{Ig} = \frac{K_{PS}}{T_{IR}}$ $T_{1g} = T_1$	**P-T2-Verhalten** $K_{Pg} = 1$ $T_{1g} = \frac{1}{K_{PS} \bullet K_{IR}}$ $T_{2g}{}^2 = \frac{T_1}{K_{PS} \bullet K_{IR}}$	**D-T2-Verhalten** $K_{Dg} = \frac{1}{K_{IR}}$ $T_{1g} = \frac{1}{K_{PS} \bullet K_{IR}}$ $T_{2g}{}^2 = \frac{T_1}{K_{PS} \bullet K_{IR}}$	0	0	0
PI	**PI-T1-Verhalten** $K_{Pg} = K_{PS} \bullet K_{PR}$ $K_{Ig} = K_{PS} \bullet K_{IR}$ $T_{1g} = T_1$	**PD-T2-Verhalten** $K_{Pg} = 1$ $K_{Dg} = \frac{K_{PR}}{K_{IR}}$ $T_{1g} = \frac{1+K_{PS} \bullet K_{PR}}{K_{PS} \bullet K_{IR}}$ $T_{2g}{}^2 = \frac{T_1}{K_{PS} \bullet K_{IR}}$	**D-T2-Verhalten** $K_{Dg} = \frac{1}{K_{IR}}$ $T_{1g} = \frac{1+K_{PS} \bullet K_{PR}}{K_{PS} \bullet K_{IR}}$ $T_{2g}{}^2 = \frac{T_1}{K_{PS} \bullet K_{IR}}$	0	0	0

P-T1-Strecke

Regler	F_O und Kennwerte	F_W und Kennwerte	F_{Zv} und Kennwerte	e_{bw}	e_{bZv}	e_b
PD	**PD-T1-Verhalten** $K_{Pg} = K_{PS} \bullet K_{PR}$ $K_{Dg} = K_{PS} \bullet K_{DR}$ $T_{1g} = T_1$	**PD-T1-Verhalten** $K_{Pg} = \frac{K_{PR} \bullet K_{PS}}{1 + K_{PS} \bullet K_{PR}}$ $K_{Dg} = \frac{K_{PS} \bullet K_{DR}}{1 + K_{PS} \bullet K_{PR}}$ $T_{1g} = \frac{T_1 + K_{DR} \bullet K_{PS}}{1 + K_{PS} \bullet K_{PR}}$	**P-T1-Verhalten** $K_{Pg} = \frac{K_{PS}}{1 + K_{PS} \bullet K_{PR}}$ $T_{1g} = \frac{T_1 + K_{DR} \bullet K_{PS}}{1 + K_{PS} \bullet K_{PR}}$	$e_{bw} = \frac{W}{1 + K_{PS} \bullet K_{PR}}$	$e_{bZv} = \frac{K_{PS} \bullet Z_V}{1 + K_{PS} \bullet K_{PR}}$	$e_b = \frac{W - (K_{PS} \bullet Z_V)}{1 + K_{PS} \bullet K_{PR}}$
PID	**PID-T1-Verhalten** $K_{Pg} = K_{PS} \bullet K_{PR}$ $K_{Ig} = K_{PS} \bullet K_{IR}$ $K_{Dg} = K_{PS} \bullet K_{DR}$ $T_{1g} = T_1$	**PDD²-T2-Verhalten** $K_{Pg} = 1$ $K_{Dg} = \frac{K_{PR}}{K_{IR}}$ $K_{Dg}{}^2 = \frac{K_{DR}}{K_{IR}}$ $T_{1g} = \frac{1 + K_{PS} \bullet K_{PR}}{K_{PS} \bullet K_{IR}}$ $T_{2g}{}^2 = \frac{T_1 + K_{DR} \bullet K_{PS}}{K_{PS} \bullet K_{IR}}$	**D-T2-Verhalten** $K_{Dg} = \frac{1}{K_{IR}}$ $T_{1g} = \frac{1 + K_{PS} \bullet K_{PR}}{K_{PS} \bullet K_{IR}}$ $T_{2g}{}^2 = \frac{T_1 + K_{DR} \bullet K_{PS}}{K_{PS} \bullet K_{IR}}$	0	0	0

P-T2-Strecke

Regler	F_O und Kennwerte	F_W und Kennwerte	F_{Zv} und Kennwerte	e_{bw}	e_{bZv}	e_b
P	**P-T2-Verhalten** $K_{Pg} = K_{PS} \bullet K_{PR}$ $T_{1g} = T_1$ $T_{2g}{}^2 = T_2$	**P-T2-Verhalten** $K_{Pg} = \frac{K_{PS} \bullet K_{PR}}{1+(K_{PS} \bullet K_{PR})}$ $T_{1g} = \frac{T_1}{1+(K_{PS} \bullet K_{PR})}$ $T_{2g}{}^2 = \frac{T_2}{1+(K_{PS} \bullet K_{PR})}$	**P-T2-Verhalten** $K_{Pg} = \frac{K_{PS}}{1+(K_{PS} \bullet K_{PR})}$ $T_{1g} = \frac{T_1}{1+(K_{PS} \bullet K_{PR})}$ $T_{2g}{}^2 = \frac{T_2}{1+(K_{PS} \bullet K_{PR})}$	$e_{bw} = \frac{W}{1+K_{PS} \bullet K_{PR}}$	$e_{bZv} = \frac{K_{PS} \bullet Z_V}{1+K_{PS} \bullet K_{PR}}$	$e_b = \frac{W-(K_{PS} \bullet Z_V)}{1+K_{PS} \bullet K_{PR}}$
I	**I-T2-Verhalten** $K_{Ig} = K_{PS} \bullet K_{IR}$ $K_{Ig} = \frac{K_{PS}}{T_{IR}}$ $T_{1g} = T_1 \quad T_{2g}{}^2 = T_2$	**P-T3-Verhalten** $K_{Pg} = 1$ $T_{1g} = \frac{1}{K_{PS} \bullet K_{IR}}$ $T_{2g}{}^2 = \frac{T_1}{K_{PS} \bullet K_{IR}}$ $T_{3g}{}^3 = \frac{T_2}{K_{PS} \bullet K_{IR}}$	**D-T3-Verhalten** $K_{Dg} = \frac{1}{K_{IR}}$ $T_{1g} = \frac{1}{K_{PS} \bullet K_{IR}}$ $T_{2g}{}^2 = \frac{T_1}{K_{PS} \bullet K_{IR}}$ $T_{3g}{}^3 = \frac{T_2}{K_{PS} \bullet K_{IR}}$	0	0	0

P-T2-Strecke

Regler	F_O und Kennwerte	F_W und Kennwerte	F_{Zv} und Kennwerte	e_{bw}	e_{bZv}	e_b
PI	**PI-T2-Verhalten** $K_{Pg} = K_{PS} \bullet K_{PR}$ $K_{Ig} = K_{PS} \bullet K_{IR}$ $T_{1g} = T_1$ $T_{2g}{}^2 = T_2$	**PD-T3-Verhalten** $K_{Pg} = 1$ $K_{Dg} = \frac{K_{PR}}{K_{IR}}$ $T_{1g} = \frac{1 + K_{PS} \bullet K_{PR}}{K_{PS} \bullet K_{IR}}$ $T_{2g}{}^2 = \frac{T_1}{K_{PS} \bullet K_{IR}}$ $T_{3g}{}^3 = \frac{T_2}{K_{PS} \bullet K_{IR}}$	**D-T3-Verhalten** $K_{Dg} = \frac{1}{K_{IR}}$ $T_{1g} = \frac{1 + K_{PS} \bullet K_{PR}}{K_{PS} \bullet K_{IR}}$ $T_{2g}{}^2 = \frac{T_1}{K_{PS} \bullet K_{IR}}$ $T_{3g}{}^3 = \frac{T_2}{K_{PS} \bullet K_{IR}}$	0	0	0
PD	**PD-T2-Verhalten** $K_{Pg} = K_{PS} \bullet K_{PR}$ $K_{Dg} = K_{PS} \bullet K_{DR}$ $T_{1g} = T_1$ $T_{2g}{}^2 = T_2$	**PD-T2-Verhalten** $K_{Pg} = \frac{K_{PS} \bullet K_{PR}}{1 + K_{PS} \bullet K_{PR}}$ $K_{Dg} = \frac{K_{DR} \bullet K_{PS}}{1 + K_{PS} \bullet K_{PR}}$ $T_{1g} = \frac{T_1 + K_{DR} \bullet K_{PS}}{1 + K_{PS} \bullet K_{PR}}$ $T_{2g}{}^2 = \frac{T_2}{1 + K_{PS} \bullet K_{PR}}$	**P-T2-Verhalten** $K_{Pg} = \frac{K_{PS}}{1 + K_{PS} \bullet K_{PR}}$ $T_{1g} = \frac{T_1 + K_{DR} \bullet K_{PS}}{1 + K_{PS} \bullet K_{PR}}$ $T_{2g}{}^2 = \frac{T_2}{1 + K_{PS} \bullet K_{PR}}$	$e_{bw} = \frac{W}{1 + K_{PS} \bullet K_{PR}}$	$e_{bZv} = \frac{K_{PS} \bullet Z_V}{1 + K_{PS} \bullet K_{PR}}$	$e_{bw} = \frac{W}{1 + K_{PS} \bullet K_{PR}}$

P-T2-Strecke

Regler	F_O und Kennwerte	F_W und Kennwerte	F_{Zv} und Kennwerte	e_{bw}	e_{bZv}	e_b
PID	**PID-T2-Verhalten** $K_{Pg} = K_{PS} \bullet K_{PR}$ $K_{Ig} = K_{PS} \bullet K_{IR}$ $K_{Dg} = K_{PS} \bullet K_{DR}$ $T_{1g} = T_1 \quad T_{2g}{}^2 = T_2$	**PDD²-T3-Verhalten** $K_{Pg} = 1$ $K_{Dg} = \frac{K_{PR}}{K_{IR}}$ $K_{Dg}{}^2 = \frac{K_{DR}}{K_{IR}}$ $T_{1g} = \frac{1 + K_{PS} \bullet K_{PR}}{K_{PS} \bullet K_{IR}}$ $T_{2g}{}^2 = \frac{T_1 + K_{DR} \bullet K_{PS}}{K_{PS} \bullet K_{IR}}$ $T_{3g}{}^3 = \frac{T_2}{K_{PS} \bullet K_{IR}}$	**D-T3-Verhalten** $K_{Dg} = \frac{1}{K_{IR}}$ $T_{1g} = \frac{1 + K_{PS} \bullet K_{PR}}{K_{PS} \bullet K_{IR}}$ $T_{2g}{}^2 = \frac{T_1 + K_{DR} \bullet K_{PS}}{K_{PS} \bullet K_{IR}}$ $T_{3g}{}^3 = \frac{T_2}{K_{PS} \bullet K_{IR}}$	0	0	0

I-Strecke

Regler	F_O und Kennwerte	F_W und Kennwerte	F_{Zv} und Kennwerte	e_{bw}	e_{bZv}	e_b
P	**I-Verhalten** $K_{Ig} = K_{IS} \bullet K_{PR}$	**P-T1-Verhalten** $K_{Pg} = 1$ $T_{1g} = \frac{1}{K_{IS} \bullet K_{PR}}$	**P-T1-Verhalten** $K_{Pg} = \frac{1}{K_{PR}}$ $T_{1g} = \frac{1}{K_{IS} \bullet K_{PR}}$	0	$e_{bZv} = \frac{Z_V}{K_{PR}}$	$e_b = -\left(\frac{Z_V}{K_{PR}}\right)$
PI	**I I^2-Verhalten** $K_{Ig} = K_{IS} \bullet K_{PR}$ $K_{Ig}{}^2 = K_{IS} \bullet K_{IR}$	**PD-T2-Verhalten** $K_{Pg} = 1$ $K_{Dg} = \frac{K_{PR}}{K_{IR}}$ $T_{1g} = \frac{K_{PR}}{K_{IR}}$ $T_{2g}{}^2 = \frac{1}{K_{IS} \bullet K_{IR}}$	**D-T2-Verhalten** $K_{Dg} = \frac{1}{K_{IR}}$ $T_{1g} = \frac{K_{PR}}{K_{IR}}$ $T_{2g}{}^2 = \frac{1}{K_{IS} \bullet K_{IR}}$	0	0	0

I-Strecke

Regler	F_O und Kennwerte	F_W und Kennwerte	F_{Zv} und Kennwerte	e_{bw}	e_{bZv}	e_b
PD	**PI-Verhalten** $K_{Pg} = K_{IS} \bullet K_{DR}$ $K_{Ig} = K_{IS} \bullet K_{PR}$	**PD-T1-Verhalten** $K_{Pg} = 1$ $K_{Dg} = \frac{K_{DR}}{K_{PR}}$ $T_{1g} = \frac{1 + K_{IS} \bullet K_{DR}}{K_{IS} \bullet K_{PR}}$	**P-T1-Verhalten** $K_{Pg} = \frac{1}{K_{PR}}$ $T_{1g} = \frac{1 + K_{IS} \bullet K_{DR}}{K_{IS} \bullet K_{PR}}$	0	$e_{bZv} = \frac{Z_V}{K_{PR}}$	$e_b = -\left(\frac{Z_V}{K_{PR}}\right)$
PID	**PII²-Verhalten** $K_{Pg} = K_{IS} \bullet K_{DR}$ $K_{Ig} = K_{PR} \bullet K_{IS}$ $K_{Ig}^{\ 2} = K_{IS} \bullet K_{IR}$	**PDD²-Verhalten** $K_{Pg} = 1$ $K_{Dg} = \frac{K_{PR}}{K_{IR}}$ $K_{Dg}^{\ 2} = \frac{K_{DR}}{K_{IR}}$ $T_{1g} = \frac{K_{PR}}{K_{IR}}$ $T_{2g}^{\ 2} = \frac{1 + K_{IS} \bullet K_{DR}}{K_{IS} \bullet K_{IR}}$	**D-T2-Verhalten** $K_{Dg} = \frac{1}{K_{IR}}$ $T_{1g} = \frac{K_{PR}}{K_{IR}}$ $T_{2g}^{\ 2} = \frac{1 + K_{IS} \bullet K_{DR}}{K_{IS} \bullet K_{IR}}$	0	0	0

I-T1-Strecke

Regler	F_O und Kennwerte	F_W und Kennwerte	F_{Zv} und Kennwerte	e_{bw}	e_{bZv}	e_b
P	**I-T1-Verhalten** $K_{Ig} = K_{IS} \bullet K_{PR}$ $T_{1g} = T_1$	**P-T2-Verhalten** $K_{Pg} = 1$ $T_{1g} = \frac{1}{K_{IS} \bullet K_{PR}}$ $T_{2g}{}^2 = \frac{T_1}{K_{IS} \bullet K_{PR}}$	**P-T2-Verhalten** $K_{Pg} = \frac{1}{K_{PR}}$ $T_{1g} = \frac{1}{K_{IS} \bullet K_{PR}}$ $T_{2g}{}^2 = \frac{T_1}{K_{IS} \bullet K_{PR}}$	0	$e_{bZv} = \frac{Z_V}{K_{PR}}$	$e_b = -\left(\frac{Z_v}{K_{PR}}\right)$
PI	**I I^2-T1-Verhalten** $K_{Ig} = K_{IS} \bullet K_{PR}$ $K_{I^2g} = K_{IS} \bullet K_{IR}$ $T_{1g} = T_1$	**PD-T3-Verhalten** $K_{Pg} = 1 \qquad K_{Dg} = \frac{K_{PR}}{K_{IR}}$ $T_{1g} = \frac{K_{PR}}{K_{IR}}$ $T_{2g}{}^2 = \frac{1}{K_{IS} \bullet K_{IR}}$ $T_{3g}{}^3 = \frac{T_1}{K_{IS} \bullet K_{IR}}$	**D-T3-Verhalten** $K_{Dg} = \frac{1}{K_{IR}}$ $T_{1g} = \frac{K_{PR}}{K_{IR}}$ $T_{2g}{}^2 = \frac{1}{K_{IS} \bullet K_{IR}}$ $T_{3g}{}^3 = \frac{T_1}{K_{IS} \bullet K_{IR}}$	0	0	0

I-T1-Strecke

Regler	F_O und Kennwerte	F_W und Kennwerte	F_{Zv} und Kennwerte	e_{bw}	e_{bZv}	e_b
PD	**PI-T1-Verhalten** $K_{Pg} = K_{IS} \bullet K_{DR}$ $K_{Ig} = K_{IS} \bullet K_{PR}$ $T_{1g} = T_1$	**PD-T2-Verhalten** $K_{Pg} = 1$ $K_{Dg} = \frac{K_{DR}}{K_{PR}}$ $T_{1g} = \frac{1 + K_{IS} \bullet K_{DR}}{K_{IS} \bullet K_{IR}}$ $T_{2g}{}^2 = \frac{T_1}{K_{IS} \bullet K_{PR}}$	**P-T2-Verhalten** $K_{Pg} = \frac{1}{K_{PR}}$ $T_{1g} = \frac{1 + K_{IS} \bullet K_{DR}}{K_{IS} \bullet K_{IR}}$ $T_{2g}{}^2 = \frac{T_1}{K_{IS} \bullet K_{PR}}$	0	$e_{bZv} = \frac{Z_V}{K_{PR}}$	$e_b = -\left(\frac{Z_v}{K_{PR}}\right)$
PID	**PI I^2-T1-Verhalten** $K_{Pg} = K_{IS} \bullet K_{DR}$ $K_{Ig} = K_{IS} \bullet K_{PR}$ $K_{I^2g} = K_{IS} \bullet K_{IR}$ $T_{1g} = T_1$ $T_{2g}{}^2 = T_2{}^2$	**PDD^2-T3-Verhalten** $K_{Pg} = 1 \qquad K_{Dg} = \frac{K_{PR}}{K_{IR}}$ $K_{D^2g} = \frac{K_{DR}}{K_{IR}}$ $T_{1g} = \frac{K_{PR}}{K_{IR}}$ $T_{2g}{}^2 = \frac{1 + K_{IS} \bullet K_{DR}}{K_{IS} \bullet K_{IR}}$ $T_{3g}{}^3 = \frac{T_1}{K_{IS} \bullet K_{IR}}$	**D-T3-Verhalten** $K_{Dg} = \frac{1}{K_{PR}}$ $T_{1g} = \frac{K_{PR}}{K_{IR}}$ $T_{2g}{}^2 = \frac{1 + K_{IS} \bullet K_{DR}}{K_{IS} \bullet K_{IR}}$ $T_{3g}{}^3 = \frac{T_1}{K_{IS} \bullet K_{IR}}$	0	0	0

I-T2-Strecke

Regler	F_O und Kennwerte	F_W und Kennwerte	F_{Zv} und Kennwerte	e_{bw}	e_{bZv}	e_b
P	**I-T2-Verhalten** $K_{Ig} = K_{IS} \bullet K_{PR}$ $T_{1g} = T_1$ $T_{2g}{}^2 = T_2{}^2$	**P-T3-Verhalten** $K_{Pg} = 1$ $T_{1g} = \frac{1}{K_{IS} \bullet K_{PR}}$ $T_{2g}{}^2 = \frac{T_1}{K_{IS} \bullet K_{PR}}$ $T_{3g}{}^3 = \frac{T_2{}^2}{K_{IS} \bullet K_{PR}}$	**P-T3-Verhalten** $K_{Pg} = \frac{1}{K_{PR}}$ $T_{1g} = \frac{1}{K_{IS} \bullet K_{PR}}$ $T_{2g}{}^2 = \frac{T_1}{K_{IS} \bullet K_{PR}}$ $T_{3g}{}^3 = \frac{T_2{}^2}{K_{IS} \bullet K_{PR}}$	0	$e_{bZv} = \frac{Z_V}{K_{PR}}$	$e_b = -\left(\frac{Z_v}{K_{PR}}\right)$
PI	**I I^2-T2-Verhalten** $K_{Ig} = K_{IS} \bullet K_{PR}$ $K_{I^2g} = K_{IS} \bullet K_{IR}$ $T_{1g} = T_1$ $T_{2g}{}^2 = T_2{}^2$	**PD-T4-Verhalten** $K_{Pg} = 1 \qquad K_{Dg} = \frac{K_{PR}}{K_{IR}}$ $T_{1g} = \frac{K_{PR}}{K_{IR}}$ $T_{2g}{}^2 = \frac{1}{K_{IS} \bullet K_{IR}}$ $T_{3g}{}^3 = \frac{T_1}{K_{IS} \bullet K_{IR}}$ $T_{4g}{}^4 = \frac{T_2{}^2}{K_{IS} \bullet K_{IR}}$	**D-T4-Verhalten** $K_{Dg} = \frac{1}{K_{IR}}$ $T_{1g} = \frac{K_{PR}}{K_{IR}}$ $T_{2g}{}^2 = \frac{1}{K_{IS} \bullet K_{IR}}$ $T_{3g}{}^3 = \frac{T_1}{K_{IS} \bullet K_{IR}}$ $T_{4g}{}^4 = \frac{T_2{}^2}{K_{IS} \bullet K_{IR}}$	0	0	0

I-T2-Strecke

Regler	F_O und Kennwerte	F_W und Kennwerte	F_{Zv} und Kennwerte	e_{bw}	e_{bZv}	e_b
PD	**PI-T2-Verhalten** $K_{Pg} = K_{IS} \bullet K_{DR}$ $K_{Ig} = K_{IS} \bullet K_{PR}$ $T_{1g} = T_1$ $T_{2g}{}^2 = T_2{}^2$	**PD-T3-Verhalten** $K_{Pg} = 1 \qquad K_{Dg} = \frac{K_{DR}}{K_{PR}}$ $T_{1g} = \frac{1 + K_{IS} \bullet K_{DR}}{K_{IS} \bullet K_{IR}}$ $T_{2g}{}^2 = \frac{T_1}{K_{IS} \bullet K_{PR}}$ $T_{3g}{}^2 = \frac{T_2{}^2}{K_{IS} \bullet K_{PR}}$	**P-T3-Verhalten** $K_{Pg} = \frac{1}{K_{PR}}$ $T_{1g} = \frac{1 + K_{IS} \bullet K_{DR}}{K_{IS} \bullet K_{IR}}$ $T_{2g}{}^2 = \frac{T_1}{K_{IS} \bullet K_{PR}}$ $T_{3g}{}^3 = \frac{T_2{}^2}{K_{IS} \bullet K_{PR}}$	0	$e_{bZv} = \frac{Z_V}{K_{PR}}$	$e_b = -\left(\frac{Z_v}{K_{PR}}\right)$
PID	**PI I^2-T2-Verhalten** $K_{Pg} = K_{IS} \bullet K_{DR}$ $K_{Ig} = K_{IS} \bullet K_{PR}$ $K_{I^2g} = K_{IS} \bullet K_{IR}$ $T_{1g} = T_1$ $T_{2g}{}^2 = T_2{}^2$	**PDD^2-T4-Verhalten** $K_{Pg} = 1 \qquad K_{Dg} = \frac{K_{PR}}{K_{IR}}$ $K_{D^2g} = \frac{K_{DR}}{K_{IR}} \qquad T_{1g} = \frac{K_{PR}}{K_{IR}}$ $T_{2g}{}^2 = \frac{1 + K_{IS} \bullet K_{DR}}{K_{IS} \bullet K_{IR}}$ $T_{3g}{}^3 = \frac{T_1}{K_{IS} \bullet K_{IR}}$ $T_{4g}{}^4 = \frac{T^2{}_2}{K_{IS} \bullet K_{IR}}$	**D-T4-Verhalten** $K_{Dg} = \frac{1}{K_{PR}}$ $T_{1g} = \frac{K_{PR}}{K_{IR}}$ $T_{2g}{}^2 = \frac{1 + K_{IS} \bullet K_{DR}}{K_{IS} \bullet K_{IR}}$ $T_{3g}{}^3 = \frac{T_1}{K_{IS} \bullet K_{IR}}$ $T_{4g}{}^4 = \frac{T^2{}_2}{K_{IS} \bullet K_{IR}}$	0	0	0