## PIDcontroller

- kP:double
- kl:double
- kD:double
- currentVelocity:double desiredVelocity:double
- currentError:double
- previousErrorSum:double = 0
- previousError:double = 0
- errorThreshold:double = 0.001
- dTime:float = 0.05
- + PIDcontroller(double,double,double,double)
- + computeError(void):double + computeVelocity(void):double + ~PIDcontroller(void)