Class Diagram

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PidController

- kp:float
- ki:float
- kd:float
- threshold:float
- cumulativeError:double
- controlError:double
- + PidController()
- + ~PidController()
- + setGainValues(float, float, float):void
- + getGainValues():vector<float>
- + computePidError(float, float, float):void
- + getControlError():float
- + setThreshold(float):void
- + printNewVeocity(float, float):void