class: PID
- _Kp: double - _Ki: double - _Kd: double
+ PID() + PID(double Set_Point, double Current_Velocity) + ~PID() + getKp(void) + getKi(void) + getKd(void) + setConstants(double Kp, double Ki, double Kd) + Compute(double Set_Point, double Current_Velocity)