Activity Diagram Karan Sutradhar Vishnuu Appaya Dhanabalan input values of kp, ki, kd and dt input values required and actual velocities currentError is calculated as the difference between required and actual velocities All the variables are fed into the PID controller Compute the currentError No While(currentError > threshold) return actualVelocity Controller Converged! Yes Set PID output = actualVelocity Compute Integral Error Compute Derivative error.

Calculate PID output.