Karan Sutradhar   Vishnuu Appaya Dhanabalan

Class Diagram

pidController
- double kp - double ki; - double kd; - double dt
+<<constructor>> pidController (double kiValue, doublekpValue, double kdValue, double dtValue) + calulateVelocity (double requiredVelocity, double actualVelocity) +changeInTime(double newDt)