

Class Diagram

pidController
<ul style="list-style-type: none">- double kp- double ki;- double kd;- double dt-double intgrError
<ul style="list-style-type: none">+<<constructor>> pidController (double kiValue, doublekpValue, double kdValue, double dtValue)+ calulateVelocity (double requiredVelocity, double actualVelocity)+getIntegralError()+setKpGain(double k)+setKiGain(double k)+setKdGain(double k)+setDtVal(double dt)+getKpGain()+getKiGain()+getKdGain()+getDtVal()+resetIntegralError()