PIDControlSystem

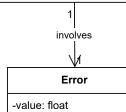
-Kp: float-Ki: float-Kd: float

-previousError: float-integral: float-minOutput: float-maxOutput: float

+PIDControlSystem(Kp: float, Ki: float, Kd: float, minOutput: float, maxOutput: float)

+compute(error: float) : : float

+reset()::void



+Error(value: float)

+getValue()::float