Initializing Kd_, Kp_ & Ki_ value using PIDController class constructor

Get the target_velocity (SP) and actual_velocity (PV)

Compute the error from SP and PV

error == 0.0

Νo

Compute the integral error using class variable accumulation_error_, error from above step and time_interval_initialized in the class

Update the class variable previous_error_

Add the three errors along with the actual_velocity to get the new actual_velocity

return newactual_velocity

Display the new actual velocity

Yes

Loic Barret Driver

Aditya Goswami Navigator

