Class Diagram

Pair A

Loic Barret
Driver

Aditya Goswami
Navigator

Pair B

Pradeep Gopal
Driver

Divyam Garg
Navigator

PIDController
-Kp_: double = 0.5 -Ki_: double = 0.001 -Kd_: double = 0.01 -previous_error_: double = 0.0 -accumulation_error_: double = 0.0 -time_interval_: double = 0.0
+ PIDController() +PIDController(double Kp_, double Ki_, double Kd_ , double time_interval_) +compute(double target_velocity, double actual_velocity): double +getPreviousError(): double +getAccumulationError(): double +getTimeInterval(): double