PID

- -double Kp
- -double Kd
- -double Ki
- -double Dt
- -double Max
- -double Min
- -double Integral -double _errorFeedback
- +PIDController(kp, ki, kd, Dt, Max, Integral,
- _errorFeedback)
 +double compute(targetSetpoint, actualVelocity)
 +void updateParameters(kp, ki, kd)
 +double getValueKi()

- +double getValueKp()
- +double getValueKd()