Group 10 Team 2

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PIDController

- kp:double
- kd:double
- ki:double
- presentError:double
- cummulativeError:double
- lastError:double

+compute(double targetSetpoint, double actualVelocity)
+PIDController(double startKP, double startKI, double startKD,
double startPresentError, double startCummulativeError, double
startLastError):PIDController

