September 24, 2019

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

