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

Initialize dt = 1

Calculate current error

Add Current error to cumulative error

change of error = current error - last error

Calculate and return output from PID controller