pid_controller
- double Kp - double Ki - double Kd - double dt
<ul> <li>+ pid_controller()</li> <li>+ pid_controller(Kp, Ki, Kd, dt)</li> <li>+ double compute(double reference_vel, double current_vel)</li> <li>+ double returndt()</li> <li>+ ~pid_controller()</li> </ul>