

## PIDcontrol

- kp : double
- ki : double
- kd : double
- dt : double
- previousError : double
- firstTime : bool

- +getKp() : double
- +getKi() : double
- +getKd() : double
- +getDt() : double
- +setKp(double)
- +setKi(double)
- +setKd(double)
- +setDt(double)
- +PIDcontrol()
- +PIDcontrol(double, double, double, double)
- +double : computeNewVelocity(double, double)
- double : calculateError(double, double)