PIDcontrol
- Kp : double   - Ki : double   - Kd : double   - Dt : double   - PreviousTime : double   - CurrentTime : double   - PreviousError : double   - FirstTime : bool
+getKp() : double   +getKi() : double   +getKd() : double   +getDt() : double   +setKp(double Kp)   +setKi(double Ki)   +setKd(double Kd)   +setDt(double Dt)   +PIDcontrol()   +PIDcontrol(double Kp, double Kd, double Ki, double Dt)   +double : ComputeNewVelocity(double TargetVelocity, double ActualVelocity)   - double : CalculateError(double TargetVelocity, double ActualVelocity)