

## PID

+ newVelocity: double - kp: double - ki: double - kd: double

- + PID (double kp, double ki, double kd)
  + IsContinous(): bool
  + setPoint(double setPoint): double
  + actualVelocity(double actualVelocity): double
- + compute(double setPoint, double actualVelocity) : double