Class Diagram

ControllerPID

k_p : doublek_i : doublek_d : double

sampling_time : doubleprev_error : doubletotal_l_error : double

+ computeVelocity(double, double): double

+ returnSamplingTime(void) : double





Take user input for k_p, k_i, k_d, target velocity and current velocity.

Call method computeVelocity

Calculate errors for each PID parameter

Calculate value of of new velocity

Print out value of new velocity

