## Robot

- botStatus: bool
- sensorType: std::string

- + Robot(): void + virtual ~Robot(): void + drive(PidController): double



## **PidController**

- + kI: double + kP: double + kD: double + error: double

- + PidController(): void + virtual ~PidController(): void + virtual PidControllerInit(double, double, double): void + virtual computeVelocity(double, double): double