```
from MotorController import *
from DRV8833 import *
from Encoder import *

desired_cps = 100    # controller setpoint
P = 1                # controller proportional gain
Ts = 20              # controller operating period in [ms]

controller = MotorController(DRV8833(19, 16), Encoder(34, 39, 0))

def callback(timer):
    global controller, desired_cps, P
    # proportional control and print actual_cps (for plotting)
    print(controller.pi_control(desired_cps, P))

timer = Timer(0)
timer.init(period=Ts, mode=Timer.UP, callback=callback(timer))
```