## **PIDcontroller**

- Kp : double- Ki : double- Kd : double

+ ComputeVelocity(double targetSetpoint,

double velocity): double

+ inputGains(params) : void

+ returnKp() : double
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## levelAlarm

- level: double

- alarm: int

thresold: doublelevelMax: double

+ levelAlarm()

+ levelControl(): void

+ returnAlarm(): int

+ ~levelAlarm()