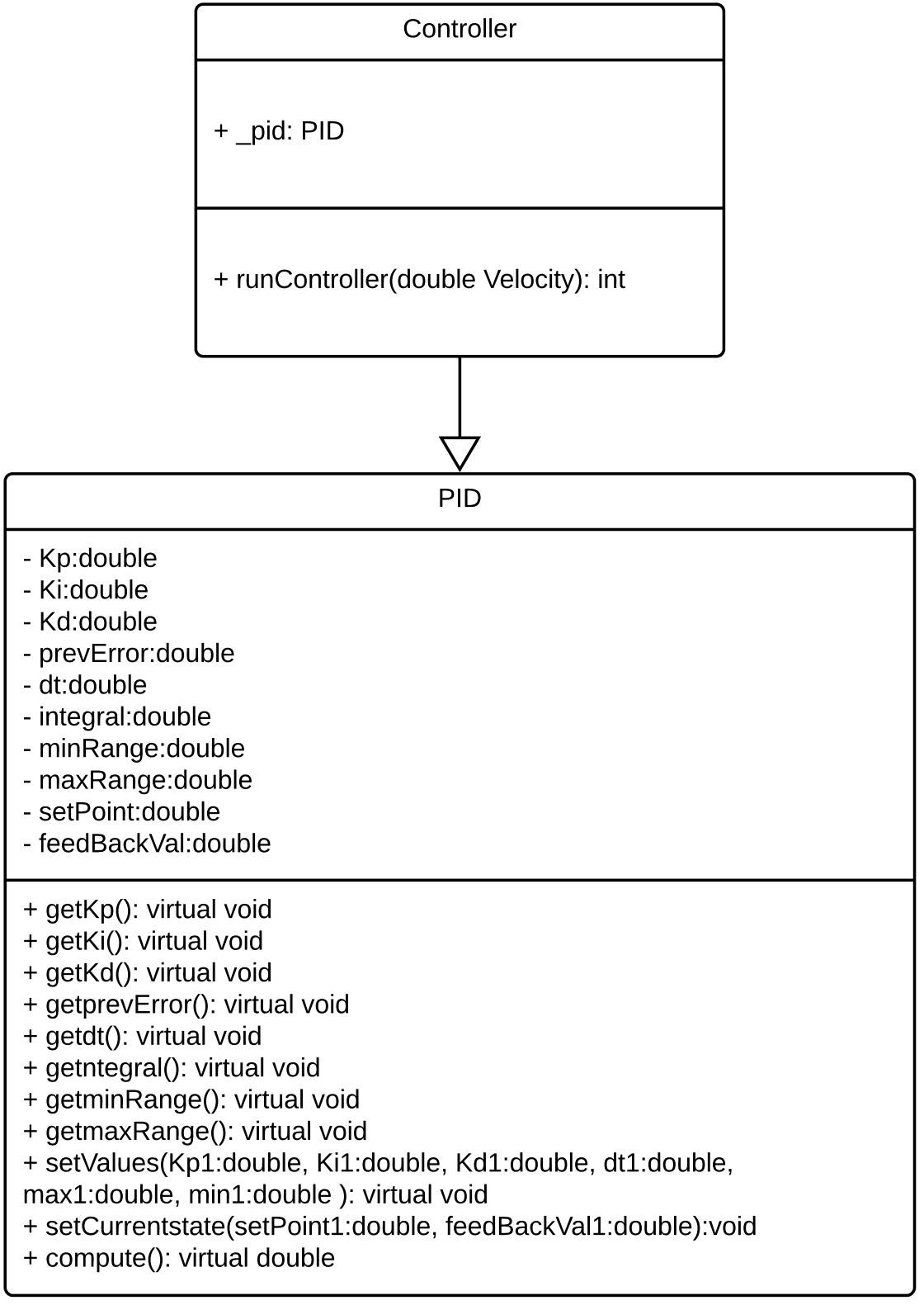
Controller
+ _pid: PID
+ runController(double Velocity): int
PID
- Kp:double
- Ki:double
- Kd:double
- prevError:double
- dt:double
- integral:double
- minRange:double
- maxRange:double
- setPoint:double
- feedBackVal:double
+ getKp(): virtual void
+ getKi(): virtual void
+ getKd(): virtual void
+ getprevError(): virtual void
+ getdt(): virtual void
+ getntegral(): virtual void
+ getminRange(): virtual void
+ getmaxRange(): virtual void
+ setValues(Kp1:double, Ki1:double, Kd1:double, dt1:double,
max1:double, min1:double ): virtual void
+ setCurrentstate(setPoint1:double, feedBackVal1:double):void
+ compute(): virtual double