UML Class Diagram For PidController Class

PidController
- kp:double =1   - ki:double =1   - kd:double =1   -setPoint:double   -previousTime:double   -previousError:double   -currentSpeed:double   -currentTime:double   -gain:double
+ calculateGain(const double actualSpeed,const double currentTime):double   +setKp(const double kp):void   +setKi(const double ki):void   +setKd(const double kd):void   +setSetPoint(const double setPoint):void;