Class **Diagram**

PIDController
- K_p_:double - K_i_:double - K_d_:double - current_velocity_:double - prev_error_:double - total_integral_error_:double - sampling_rate_:double
+ PIDController(double, double, double): void

- + compute(double, double): void
- + get_current_velocity(void): double

Activity Diagram

