

## PIDController

- kp: double
- kd: double
- ki: double
- setpoint: double
- integral\_error: double
- out\_min: double
- out\_max: double
- sampling\_time: double
- prev\_error\_: double

- +PIDController(...)
- +calculate(in setpoint:double,  
in measurement:double): double

### Responsibilities

- Computes control signal using PID algorithm