

## drone\_swarm::PIDController

- + PIDController()
- + PIDController()
- + setGains()
- + setLimits()
- + setIntegralLimits()
- + setIntegralThreshold()
- + calculate()
- + reset()
- + calculateWithWindupProtection()
- + getProportional()
- + getIntegral()
- + getDerivative()
- + getLastError()
- + getIntegralAccumulator()