PID

- k_p: double
- k_i: double
- k_d: double
- old_error: double
- min: double
- max: double

+ get k_p(): double
+ get k_i(): double
+get k_d(): double
+CaculateCummulativeError(double):double
+ErrorDerivativeCalculation(double):double
+ ComputeVelocity(double,double): double
+ checkParams():