PID

- Kp:double
- Kd:double
- Ki:double
- dt:double
+ integral:double
+ prev_error:double
+ derivative:double
+ setpoint:double
+ current_value:double

+ PropControl(error):double
+ IntControl(error):double
+ DerControl(error):double
+ compute_error(setpoint,val):double
+ calcOutput(error):double