

PID

- Kp:double
- Kd:double
- Ki:double
- dt:double
- integral:double
- error:double

- + prop_control(Kp,error):double
- + int_control(Ki, error, dt):double
- + diff_control(Kd, error, dt):double
- + calc_error(prop_out,int_out,diff_out):double