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pidController
- kp: double
- ki: double
- kd: double
- target_velocity: double
- dt: double
+ pidController(double,double,double,double)
+ Compute(double,std::vector<double>): double
+ GetKp(): double
+ GetKi(): double
+ GetKd(): double
+ SetKp(double): void
+ SetKi(double): void
+ SetKd(double): void
+ CalculatePError(double): double
+ CalculateIError(std::vector<double>, double): double
+ CalculateDError(double,std::vector<double>): double