

PID_Controller

- kp : double
- ki : double
- kd : double
- required_vel : double = 0
- initial_vel : double = 0
- time_step : double

- + set_required_velocity(required_velocity : double = 0) : bool
- + compute_pid(present_vel : double, req_vel : double)
- + PID_Controller()
- + PID_Controller(initial_velocity : double, time_step : double)