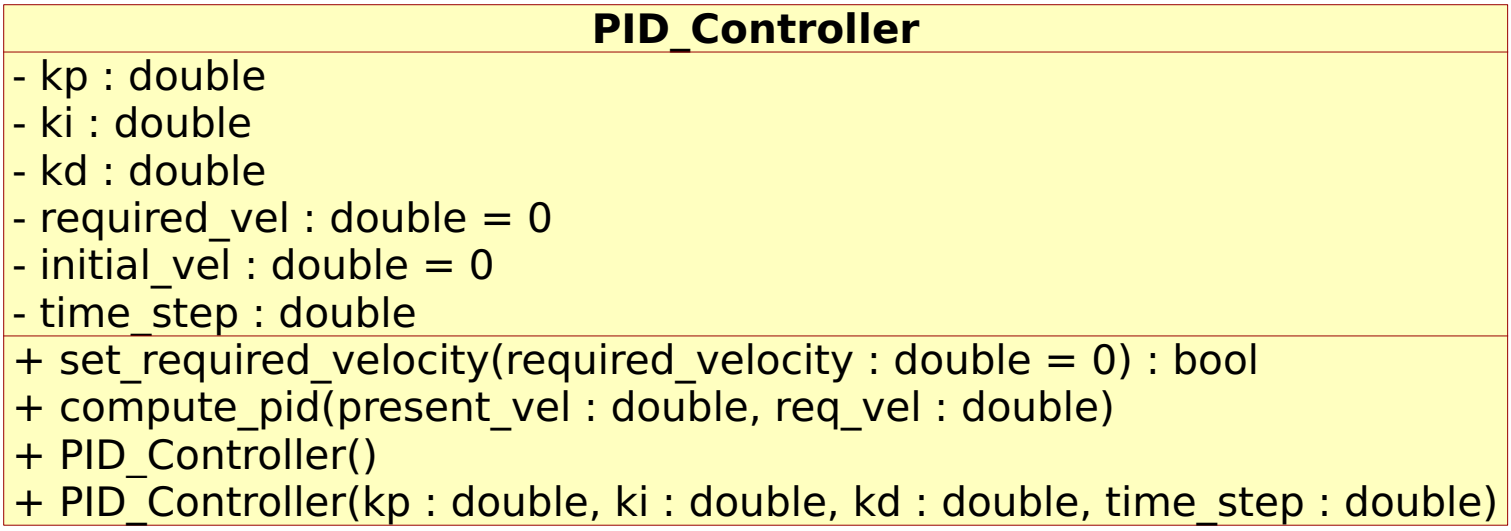
PID_Controller
- kp : double
- ki : double
- kd : double
- required_vel : double = 0
- initial_vel : double = 0
- time_step : double
+ set_required_velocity(required_velocity : double = 0) : bool
+ compute_pid(present_vel : double, req_vel : double)
+ PID_Controller()
+ PID_Controller(kp : double, ki : double, kd : double, time_step : double)