UML Class Dlagram PID Rohith Jayarajan UID: 115458437 **PIDController** - Kp: double - Ki: double - Kd: double - dt: double + PIDController(void): void + virtual~PIDController(void): void + computeControlSignalInfo(ControlSystemHelper&,double, double): double + computeTrackingError(ControlSystemHelper&, double): double + setGainKp(double): void + setGainKi(double): void + setGainKd(double): void + setTimeStep(double): void + getGainKp(void): double + getGainKi(void): double + getGainKd(void): double + getTimeStep(void): double ControlSystemHelper - Kp: double - Ki: double - Kd: double - dt: double - outputVelocity: double +ControlSystemHelper(void): void + virtual ~ControlSystemHelper(void): void + virtual compute Velocity (double, double, double, double, double, double, double): double + virtual computeError(double): double