

PidController

- Kp:float
- Kd:float
- Ki:float
- delta time:const float
- clipper_max_value:const float
- start_state:float
- total error:float
- current_state:float
- + compute(float, float):void
- + compute_step(void):float
- + clipper(float):float
- + Pid_controller(void):None