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UML CLASS DIAGRAM

AckermannController

- d : vector<double>
- theta: int
- v : double
- I: double
- + << constructor >> AckermannController(d: vector < double >, theta: int)
- + getD(): vector<double>
- + getTheta(): int
- + setD(d : vector<double>) : void
- + setTheta(theta: int): void
- + computeLh(v : double) : double
- + controlConstants(v : double) : vector<double>
- + computeSteering(d: vector<double>, I: double): double
- + driveVelocitites(theta: int): vector<double>