

**«Domain»
Steering**

- rampUp: int
- rampDown: int
- brakeForce: int
- speedReq: int
- speedAct: int
- pwm: int
- analyseInput()
- turn(int value): int
- setPWM(int pwm): bool

- + userInput(input): bool
- + goForward(int speed): bool
- + goBackward(int speed): bool
- + awaitNewInput()
- + blockUser(): bool
- + brake(): bool
- + turnLeft(): bool
- + turnRight(): bool