

«Domain»  
**Steering**

- pwm\_: int
- direction\_: bool
- minServoPWM\_: int
- maxServoPWM\_: int
- dataClassPtr\_: Data\*
- dState\_: double
- iState\_: double
- iMax\_: double
- iMin\_: double
- iGain\_: double
- pGain\_: double
- dGain\_: double
- error\_: double
- pTemp\_: double
- dTemp\_: double
- iTemp\_: double

- + userInput(unsigned char speedForward, unsigned char speedBackward, char turn, char brake): int
- brake(): int
- softbrake(): int
- turn(int value): int
- setPWM(unsigned char speedForward, unsigned char speedBackward): bool
- updatePWM(): int