

Analysis
+ converge(): void

UserInterface
+ target_velocity: double
+ target_heading: double
+ getTargets(): std::vector<double>

Robot
+ wheel_base: double
+ wheel_track: double
+ wheel_radius: double
+ robot_heading: double
+ robot_velocity: double
+ inner_wheel_velocity: double
+ outer_wheel_velocity: double
+ drive(double,double): void

Visualization
+ show(double,double): void

Controller
+ max_steering_angle: double
+ max_throttle: double
+ computeSteering(double, double): double
+ computeThrottle(double, double): double

