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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