# Updated UML Diagram Govind Ajith Kumar Justin Albrecht Pradeep Gopal

Analysis	
+ converge(): void	Text

## UserInterface

- target\_velocity: double
- target\_heading: double
- + getTargets(): std::vector<double>

# Robot

- wheel\_base: double
- wheel\_track: double
- wheel\_radius: double
- com\_offset: double
- robot\_heading: double
- robot\_velocity: double
- inner\_wheel\_velocity: double
- outer\_wheel\_velocity: double
- + drive(double,double): void



# Controller

- max\_steering\_angle: double
- Kp\_theta: double
- Ki\_theta: double
- Kd\_theta: double
- Kp\_s: double
- Ki\_s: double
- Kd\_s: double
- heading\_error: std::vec<double>
- speed\_error: std::vec<double>
- + computeError(double, double): void
- + computeSteering(): double
- + computeThrottle(): double

# Visualization

+ show(double,double): void