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UML CLASS DIAGRAM RAJ SHINDE PRASHEEL RENKUNTLA

SteerAlgorithm **Navigation** - kp_ : double - shaftLength : double - ki _ : double - maxTurnVelocity_: double - kd : double - wheelCircumference_: double - diffTime : double - IWheelAngle_: double - error : double - rWheelAngle_ : double - previousError _ : double - heading : double - maxMotorSpeed : double robotAngle_: double + motorDirection : boolean corrRadius_ : double + Navigation(): none + SteerAlgorithm(): none + ~Navigation(): none + ~SteerAlgorithm(): none + caclulate(double, double) : double + getCorrRadius(): double + getkp_() : double + setCorrRadius(double) : boolean + getki_() : double + arcLength(double, double): double + getkd (): double + turnTime(double, double) : double + setkp (double): boolean + changeWheelAngle(double, double) : double + setki_(double) : boolean + resetWheelAngles(): bool + setkd_(double) : boolean + steer(double, double) : double