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UML CLASS DIAGRAM RAJ SHINDE PRASHEEL RENKUNTLA

SteerAlgorithm **Navigation** - kp_: double - shaftLength_: double - ki _ : double - shaftDistance : double - kd : double - maxTurnVelocity_ : double - diffTime_ : double - wheelCircumference_: double - error _ : double - IWheelAngle_: double - previousError _ : double - rWheelAngle_: double - heading_ : double - maxMotorSpeed _ : double + motorDirection : boolean - robotAngle_ : double - corrRadius : double + Navigation(): none + ~Navigation() : none + SteerAlgorithm(): none + caclulate(double, double, int) : double + ~SteerAlgorithm(): none + getkp_(): double + getCorrRadius_() : double + getki_() : double + setCorrRadius_(double) : boolean + getkd_() : double + arcLength(double, double) : double + setkp_(double) : boolean + changeWheelAngle(double, double, double): double + setki (double): boolean + resetWheel(): boolean + setkd_(double): boolean + turnTime(double, double) : double