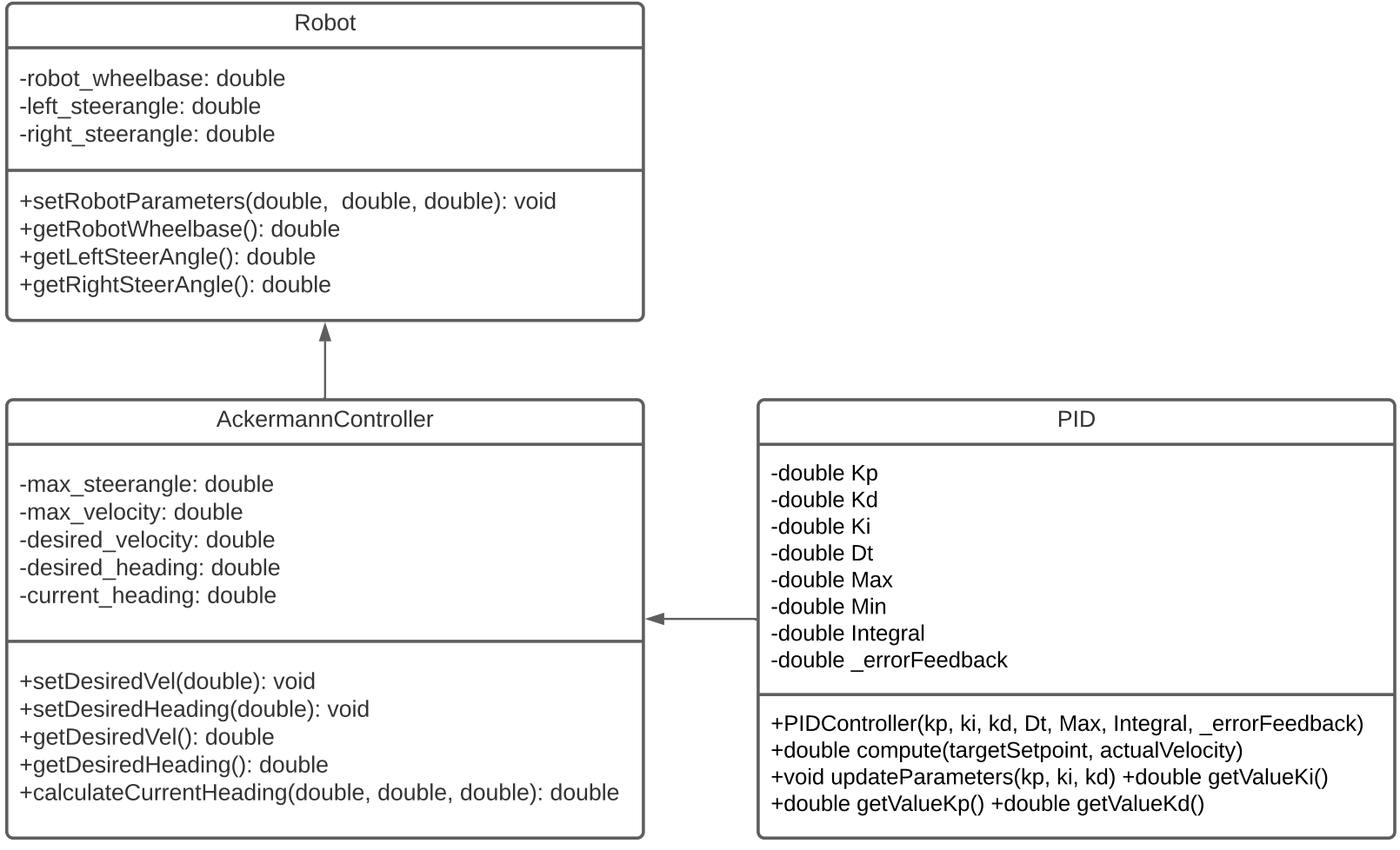
Robot
-robot_wheelbase: double
-left_steerangle: double
-right_steerangle: double
+setRobotParameters(double, double, double): void
+getRobotWheelbase(): double
+getLeftSteerAngle(): double
+getRightSteerAngle(): double
AckermannController
-max_steerangle: double
-max_velocity: double
-desired_velocity: double
-desired_heading: double
-current_heading: double
+setDesiredVel(double): void
+setDesiredHeading(double): void
+getDesiredVel(): double
+getDesiredHeading(): double
+calculateCurrentHeading(double, double, double): double
PID
-double Kp
-double Kd
-double Ki
-double Dt
-double Max
-double Min
-double Integral
-double _errorFeedback
+PIDController(kp, ki, kd, Dt, Max, Integral, _errorFeedback)
+double compute(targetSetpoint, actualVelocity)
+void updateParameters(kp, ki, kd) +double getValueKi()
+double getValueKp() +double getValueKd()