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Мар		AckermanKinematicModel
-mapBounds:Point -currCarCoords:Point3f -startCoords:Point3f -destinationCoords:Point3f -currMapImage:Mat -currCoords:Point3f -length:double -width:double		- wheelBase : double - axleWidth : double - steeringAngle : double - carVelocity : double - carState : Point3f
+SetStartCoordinates(inputCoordin +SetDestinationCoordinates(inputCoord bool +UpdateRobotLocation(inputCoord +GetRobotCoordinates():returnTyp +InitializeMap(Point, length, width): +CheckReachedDestination():retur +CheckValidCoordinates(): returnTy +DisplayMapImage():returnType bo	coordinates):returnType inates):returnType bool e Point3f returnType bool nType bool ype bool	+ getWheelBase(): double + getAxleWidth(): double + getSteeringAngle(): double + getCarVelocity(): double + getCarState(): Point3f + setWheelBase(double I): bool + setAxleWidth(double w): bool + setSteeringAngleAndCarVelocity(Eigen::Vector2d controllerOutput): bool + setCarState(Point3f state): bool + calcAckermanParameters(): Point3f + checkAngleConstraints(): bool
		ID
	 kp : Eigen::MatrixXd ki : Eigen::MatrixXd kd : Eigen::MatrixXd lastError : Eigen::Vector3d errorSum : Eigen::Vector3d 	
	+ getKp(): Eigen::MatrixXd + getKi(): Eigen::MatrixXd + getKd(): Eigen::MatrixXd + setKp(kpln: Eigen::MatrixXd): + setKi(kiln: Eigen::MatrixXd): + setKd(kdln: Eigen::MatrixXd): + getControllerOutput(targetStat Eigen::Vector3d): Eigen::Vector + resetErrors(): void	gen::Vector3d, currentState :