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getWheelBase()	getAxleWidth()	getSteeringAngle()	getCarVelocity()	getCarState()	setWheelBase(double I)	setAxleWidth(double w)	setSteeringAngle(double phi)	setCarVelocity(double s)	setCarState(std::vector <double> state)</double>	calcAckermanParameters()	checkAngleContraints()
return the wheelBase attribute	return the axleWidth attribute	return the steeringAngle attribute	return the carVelocity attribute	return the carState attribute	get the user input of wheel base length I No Yes set the attribute wheelBase to I and return true	get the user input of axle width w No Set the attribute axleWidth to w and return true	check the condition for the angle phi to be valid No if phi is less than or equal to 45 Yes set the attribute steeringAngle to phi and return true	check the car velocity s for validity No Set the attribute carVelocity to s and return true	check the validity of the elements of state, i.e x-coordinate, y-coordinate and heading angle if (x-coordinate >=0) and (y-coordinate>=0) and (0<= heading angle <= 360) set the attribute carState to state and return true	get the values of wheelBase, steeringAngle and carVelocity though getter methods calculate the change in x-coordinate, change in y-coordinate and change in car heading angle Store this changes into some local varaibles access the carState through getter method, and access the 3 elements x-coordinate, y-coordinate and car heading angle through vector indexing Update x-coordinate, y-coordinate and car heading angle using current values and change in those values calculated above return these new updated variables for this method	get the wheelBase, axleWidth and steeringAngle attributes,through appropriate getter methods calculate inner and outer wheel angles if both angle are less than 45 degress return false return true