

Class Diagram

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AckermanKinematicModel

- wheelBase : double
- axleWidth : double
- steeringAngle : double
- carVelocity : double
- carState : std::vector<double>

+ getWheelBase() : double
+ getAxleWidth() : double
+ getSteeringAngle() : double
+ getCarVelocity() : double
+ getCarState() : std::vector<double>
+ setWheelBase(double l) : bool
+ setAxleWidth(double w) : bool
+ setSteeringAngle(double phi) : bool
+ setCarVelocity(double s) : bool
+ setCarState(std::vector<double> state) : bool
+ calcAckermanParameters() : std::vector<double>
+ checkAngleConstraints() : bool