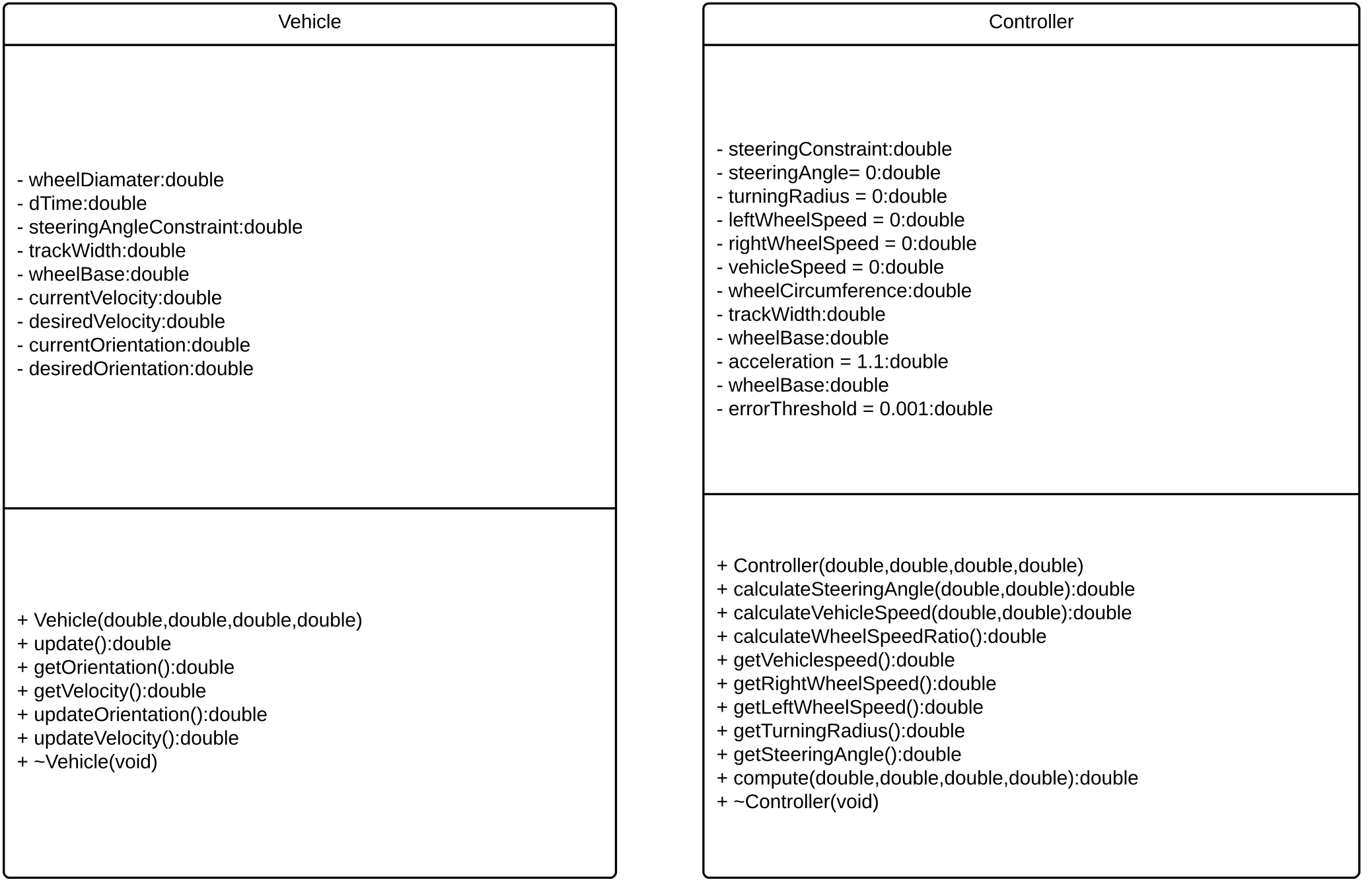
Vehicle
- wheelDiamater:double
- dTime:double
- steeringAngleConstraint:double
- trackWidth:double
- wheelBase:double
- currentVelocity:double
- desiredVelocity:double
- currentOrientation:double
- desiredOrientation:double
+ Vehicle(double,double,double,double)
+ update():double
+ getOrientation():double
+ getVelocity():double
+ updateOrientation():double
+ updateVelocity():double
+ ~Vehicle(void)
Controller
- steeringConstraint:double
- steeringAngle= 0:double
- turningRadius = 0:double
- leftWheelSpeed = 0:double
- rightWheelSpeed = 0:double
- vehicleSpeed = 0:double
- wheelCircumference:double
- trackWidth:double
- wheelBase:double
- acceleration = 1.1:double
- wheelBase:double
- errorThreshold = 0.001:double
+ Controller(double,double,double,double)
+ calculateSteeringAngle(double,double):double
+ calculateVehicleSpeed(double,double):double
+ calculateWheelSpeedRatio():double
+ getVehiclespeed():double
+ getRightWheelSpeed():double
+ getLeftWheelSpeed():double
+ getTurningRadius():double
+ getSteeringAngle():double
+ compute(double,double,double,double):double
+ ~Controller(void)