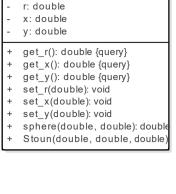
Hill dispx: double dispxy: double dispy: double hight: double x: double y: double Gauss(double, double): double get_dispx(): double {query} get dispxy(): double {query} get_dispy(): double {query} get_hight(): double {query} get_x(): double {query} get_y(): double {query} Hill(double, double, double, double, double) set dispx(double): void set_dispxy(double): void set dispy(double): void set_hight(double): void set_x(double): void set_y(double): void

r. double x1: double x2: double v1: double y2: double cylinder(double, double): double get_r(): double {query} get_x1(): double {query} get_x2(): double {query} get_y1(): double {query} get_y2(): double {query} Log(double, double, double, double, double) set_r(double): void set_x1(double): void set_x2(double): void set_y1(double): void set_y2(double): void

Loa



GetSSVertex(Vertex): Vertex

GetSWVertex(Vertex): Vertex

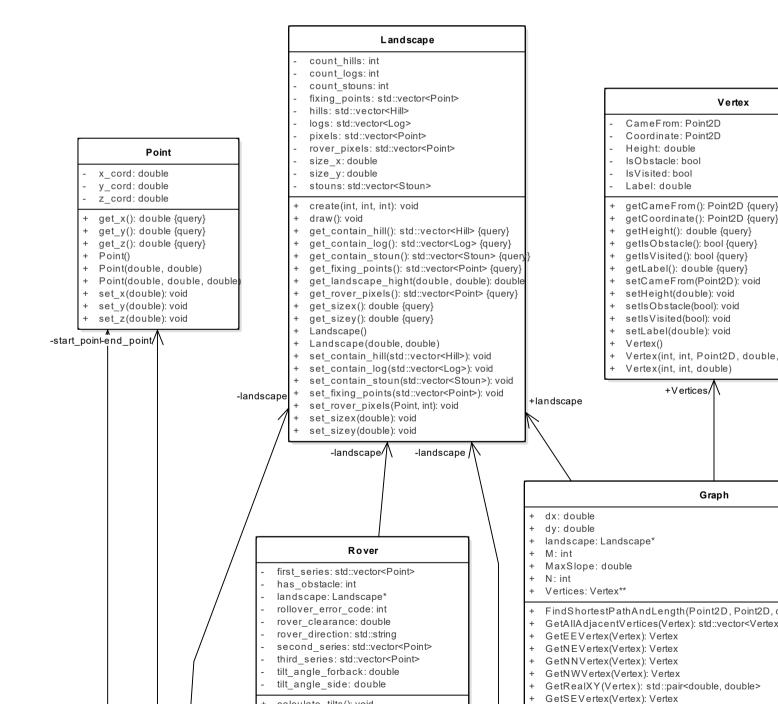
GetWWVertex(Vertex): Vertex

~Graph()

GetValidNeighbors(Vertex): std::vector<Vertex>

Graph(double, double, int, int, Landscape*)

Stoun



calculate_tilts(): void

check_obstacle(): void

check_tilts(): bool

change_direction(std::string): void

get_direction(): std::string {query}

get_roll_code(): int {query}

net tilt anale forhack() dou

