DiagrammeDeClasses_Proxy

Package in package 'Model'

DiagrammeDeClasses_Proxy diagram

Class diagram in package 'DiagrammeDeClasses_Proxy'
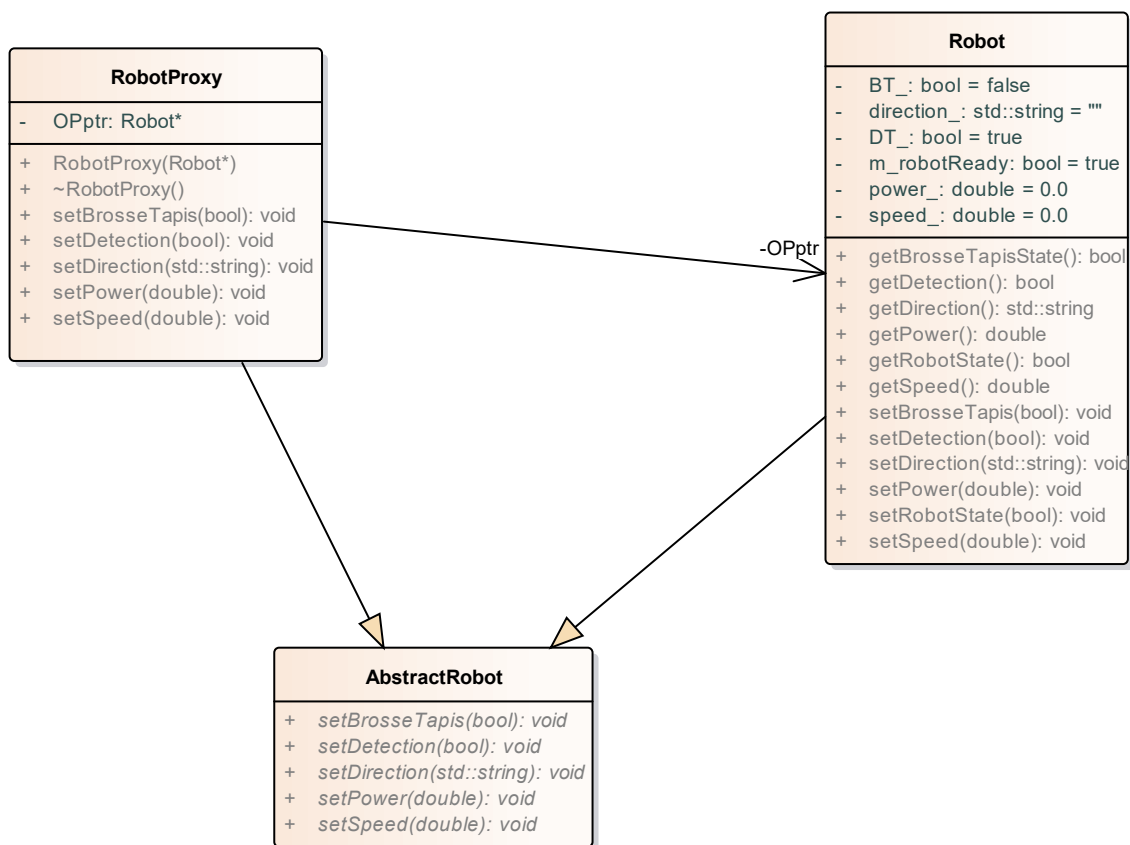
Figure 1: DiagrammeDeClasses_Proxy

AbstractRobot

Class in package 'Class Model'

INCOMING STRUCTURAL RELATIONSHIPS
⇒ Generalization from RobotProxy to AbstractRobot
[Direction is 'Source -> Destination'.]

INCOMING STRUCTURAL RELATIONSHIPS

➡ Generalization from Robot to AbstractRobot

[Direction is 'Source -> Destination'.]

OPERATIONS

◆ setBrosseTapis (BT : bool) : void Public

[Is static False. Is abstract True. Is return array False. Is query False. Is synchronized False.]

◆ setDetection (DT : bool) : void Public

[Is static False. Is abstract True. Is return array False. Is query False. Is synchronized False.]

◆ setDirection (direction : std::string) : void Public

[Is static False. Is abstract True. Is return array False. Is query False. Is synchronized False.]

◆ setPower (power : double) : void Public

[Is static False. Is abstract True. Is return array False. Is query False. Is synchronized False.]

◆ setSpeed (speed : double) : void Public

[Is static False. Is abstract True. Is return array False. Is query False. Is synchronized False.]

Robot

Class in package 'Class Model'

Robot
Version 1.0 Phase 1.0 Proposed
bodiaa created on 2019-06-18. Last modified 2019-06-18

OUTGOING STRUCTURAL RELATIONSHIPS

⬅ Generalization from Robot to AbstractRobot

[Direction is 'Source -> Destination'.]

ATTRIBUTES

◆ BT_ : bool Private = false

[Is static False. Containment is Not Specified.]

◆ direction_ : std::string Private = ""

[Is static False. Containment is Not Specified.]

◆ DT_ : bool Private = true

[Is static False. Containment is Not Specified.]

◆ m_robotReady : bool Private = true

ATTRIBUTES

[Is static False. Containment is Not Specified.]

◆ power_ : double Private = 0.0

[Is static False. Containment is Not Specified.]

◆ speed_ : double Private = 0.0

[Is static False. Containment is Not Specified.]

ASSOCIATIONS

✎. Association (direction: Source -> Destination)

Source: Public (Class) RobotProxy   Target: Private OPptr (Class) Robot

OPERATIONS

◆ getBrosseTapisState () : bool Public

[Is static False. Is abstract False. Is return array False. Is query False. Is synchronized False.]

◆ getDetection () : bool Public

[Is static False. Is abstract False. Is return array False. Is query False. Is synchronized False.]

◆ getDirection () : std::string Public

[Is static False. Is abstract False. Is return array False. Is query False. Is synchronized False.]

◆ getPower () : double Public

[Is static False. Is abstract False. Is return array False. Is query False. Is synchronized False.]

◆ getRobotState () : bool Public

[Is static False. Is abstract False. Is return array False. Is query False. Is synchronized False.]

◆ getSpeed () : double Public

[Is static False. Is abstract False. Is return array False. Is query False. Is synchronized False.]

◆ setBrosseTapis (BT : bool) : void Public

[Is static False. Is abstract False. Is return array False. Is query False. Is synchronized False.]

◆ setDetection (DT : bool) : void Public

[Is static False. Is abstract False. Is return array False. Is query False. Is synchronized False.]

◆ setDirection (direction : std::string) : void Public

[Is static False. Is abstract False. Is return array False. Is query False. Is synchronized False.]

◆ setPower (power : double) : void Public

[Is static False. Is abstract False. Is return array False. Is query False. Is synchronized False.]

OPERATIONS

🔶 setRobotState (robotState : bool) : void Public
[Is static False. Is abstract False. Is return array False. Is query False. Is synchronized False.]

🔶 setSpeed (speed : double) : void Public
[Is static False. Is abstract False. Is return array False. Is query False. Is synchronized False.]

RobotProxy

Class in package 'Class Model'

RobotProxy
Version 1.0 Phase 1.0 Proposed
bodiaa created on 2019-06-18. Last modified 2019-06-18

OUTGOING STRUCTURAL RELATIONSHIPS

⬅ Generalization from RobotProxy to AbstractRobot
[Direction is 'Source -> Destination'.]

ATTRIBUTES

🔷 OPptr : Robot* Private
[Is static False. Containment is Not Specified.]

ASSOCIATIONS

✏ Association (direction: Source -> Destination)

Source: Public (Class) RobotProxy   Target: Private OPptr (Class) Robot

OPERATIONS

🔶 RobotProxy (OPptr : Robot*) : Public
[Is static False. Is abstract False. Is return array False. Is query False. Is synchronized False.]

🔶 ~RobotProxy () : Public
[Is static False. Is abstract False. Is return array False. Is query False. Is synchronized False.]

🔶 setBrosseTapis (TP : bool) : void Public
[Is static False. Is abstract False. Is return array False. Is query False. Is synchronized False.]

🔶 setDetection (DT : bool) : void Public
[Is static False. Is abstract False. Is return array False. Is query False. Is synchronized False.]

🔶 setDirection (direction : std::string) : void Public

OPERATIONS

[Is static False. Is abstract False. Is return array False. Is query False. Is synchronized False.]

◆ setPower (power : double) : void Public

[Is static False. Is abstract False. Is return array False. Is query False. Is synchronized False.]

◆ setSpeed (speed : double) : void Public

[Is static False. Is abstract False. Is return array False. Is query False. Is synchronized False.]