Simulator class

properties

Robot

Map

function obj = Simulator(m,l,r)

start

obj.loadMap(m);

obj.loadRobot(r,l);

stop

function loadMap(obj,m)

start

obj.Map = m;

figure(1);

% set axis limit

gca;

xlim([0 m.Width]);

ylim([0 m.Height]);

zlim([0 1.3]);

stop

function loadRobot(obj,r,l)

start

obj.Robot = r;

obj.Robot.Xlim = obj.Map.Width;

obj.Robot.Ylim = obj.Map.Height;

obj.Robot.BotFus = l;

obj.Robot.runRobot;

stop