```
RoboControl
                 Λ
          NewRoboControl
        m_stopCruisingNow

    m_isCruising

        m_cruiseThread
       + NewRoboControl()
       + ~NewRoboControl()
       + IsOnTarget()
       + cruisetoBias()
       + RandomMove()
       + drivePath()
       + setSpeed()
       + getDirection()
       + getDiffAngle()
       + getSpeedP()
       + getSpeedPt()
       + getSpeedT()
       + degToRad()
       + IsOnTarget()
                 Δ
            TeamRobot
# m_defaultPos
# m coordCalib
# m_map
# m_ball
# m_pathFinder
# m_display
# m_roboObstacles
# m roboObstaclePos
# m ballObstacles
# m_ballObstaclePos
# m_penaltyAreaObstacles
# m borderObstacles
# m_pathFinderPath
# m_prevFormation
# m_areaObstacle
# m_path
# m_q
# m_actionPerformed
# m_go_x
# m_go_y
# m_ballPm
m_thread

    m_targetPos

    m_checkSpeedFinishNow

m_targetSpeed
+ TeamRobot()
+ ~TeamRobot()
+ getDefaultPosition()
+ setDefaultPositionX()
+ setDefaultPositionY()
+ setDefaultPosition()
+ getCoordinatesCalibrer()
+ getBall()
+ getMapValue()
+ getMap()
+ setMapValue()
+ setMap()
+ GiveDisplay()
+ KickOff()
+ KickPenalty()
+ Rotation()
+ KickBall()
+ KickMovingBall()
+ ShouldKick()
+ ShouldGoalKick()
+ setNextCmd()
+ setCmdParam()
+ performCmd()
# AddBorderObstaclesToPathFinder()
# UpdatePathFinder()
# ComputePath()
# FollowPath()
# AddObstacleForFormation()
# IsPathOK()
# AngleDiff()
Checkspeed()
                 Λ
            PlayerTwo
    m_ballpt
    · m_q
    m_path
    - m_nextCmd
    m_kickOffParam
    m_defendpm

    DEFENSE_LINE

    + PlayerTwo()
    + setNextCmd()
    + setCmdParam()
    + performCmd()

    AddObstacleForFormation()
```