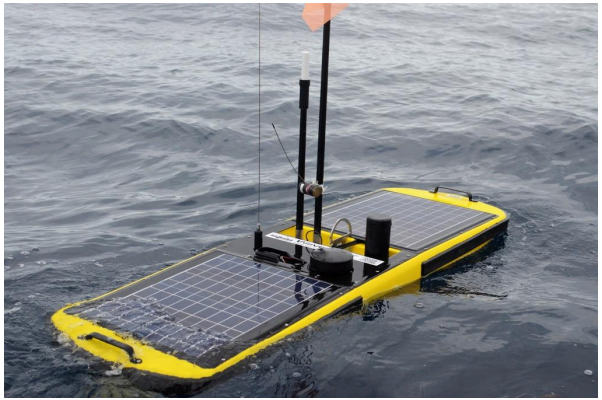
1. Robot (Abstrata)
    1.1. Unmanned Aerial Vehicle
    1.2. Unmanned Ground Vehicle
    1.3. Unmanned Marine Vehicle

1. Unmanned Aerial Vehicle
    a. Efficiency = 2

2. Unmanned Ground Vehicle
    a. Efficiency = 3

3. Unmanned Marine Vehicle
    a. Efficiency = 4



- Class
  - Sub/Superclass
  - Virtual Class
- Struct
- Dynamic Arrays
  - Foreach
- Queue
  - Sort
  - Sort with
  - RSort
- Function Overload
- Function Overwrite
- Write
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```
# Errors: 0, Warnings: 9
# vsim -novopt UnmannedRobots.test
# Start time: 13:04:34 on Apr 01,2019
# ** Warning: (vsim-8891) All optimizations are turned off because the -novopt switch is in effect. This will cause your simulation to run very slowly. If you are using this switch to preserve visibility for Debug or PLI features please see the User's Manual section on Preserving Object Visibility with vopt.
# Refreshing /home/darlan/Master/2019_1/VerificacaoFuncionalDeSistemasDigitais/Playground/UnmannedRobot/UnmannedRobots.test
# Refreshing /home/darlan/Master/2019_1/VerificacaoFuncionalDeSistemasDigitais/Playground/UnmannedRobot/UnmannedRobots.UnmannedRobots
# Loading sv_std.std
# Loading UnmannedRobots.UnmannedRobots
# Loading UnmannedRobots.test
################################################################
# Robot name: uav1
# Robot amount of devices:          2
# Device          0: Localization
# Device          1: Motion
# My efficiency is:          2
#
# Robot: uav1
# My mission is to fly through the skies.
################################################################
#
################################################################
# Robot name: ugv1
# Robot amount of devices:          2
# Device          0: Localization
# Device          1: Motion
# My efficiency is:          3
#
# Robot: ugv1
# My mission is to explore the ground surface.
################################################################
#
################################################################
# Robot name: umv1
# Robot amount of devices:          2
# Device          0: Localization
# Device          1: Motion
# My efficiency is:          4
#
# Robot: umv1
# My mission is to navigate through the oceans.
################################################################
#
# Robot: uav1 Efficiency:          2
# Robot: umv1 Efficiency:          4
# Robot: ugv1 Efficiency:          3
################################################################ After Reverse Sorting
#
# Robot: umv1 Efficiency:          4
# Robot: ugv1 Efficiency:          3
# Robot: uav1 Efficiency:          2
################################################################
#
# ** Note: implicit $finish from program    : TB/../SW/test.sv(47)
#    Time: 0 ns  Iteration: 0  Instance: /test
# 1
# Simulation stop requested.
```