FlightPlanProperties

Properties
- dtto: double
- flightplan_id: uint32
- operator: Operator
- priority: uint8
- route
- sent: uint8
- status: int8
- uav: UAVProperties

Methods
- abstractionLayer
- ⊕ abstractionLayerUplan
- FlightPlanProperties
- ⊕ generateRandomRoute
- parseToROSMessage

Operator

Properties
- drone_garage: UAVProperties
- operator_id: uint32
- operator_name: string
- ros_node
- ros_reg_fp
- ros_reg_operator
- ros_reg_uav

Methods
- Operator
- regNewDrone
- regNewFP
- sendFlightPlan

SimulationProcesser

Properties
- num_uavs
- S_Monitoring
- S_Registry

Methods
- checkConflictsComplete
- checkConflictsFast
- computeFpFollowingError
- computeFpTraveledDistance
- filterUavTelemetryByTime
- getFpById
- getFpWaypoints
- getOperatorById
- getUavById
- getUavTelemetry
- SimulationProcesser
- telemetryViewer

UAVProperties

Properties
- drone_id: uint32
- init_loc
- model: string
- operator: Operator
- ros_fp_pub
- ros_telemetry_sub
- status: int8
- UAV_reg_message

Methods
- pubsubToFlightPlan
- UAVProperties

UTMAirspace

Properties
- finish_simulation_time
- finish_simulation_timer
- Gclock
- GClock_sub
- GClock_Upt_timer
- gct_Monitoring
- gct_Registry
- rosMasterIp: string
- rosMasterPort: uint32
- S_Monitoring: S_Monitoring
- S_Registry: S_Registry

Methods
- checkIfTimeToFinishSimulation
- connectWithROSMaster
- finishSimulation
- pauseSimulation
- removeAllModelsFromSimula…
- setFinishSimulationTime
- updateGclock
- UTMAirspace

WorldModel

Properties
- buildings
- file
- filename
- matrix_fig
- world_fig
- world_occupancy
- world_size

Methods
- check
- getRoute
- getStep
- hasClearAround
- matind2pos
- pos2matind
- randomMatInd
- readWorldFromFile
- WorldModel