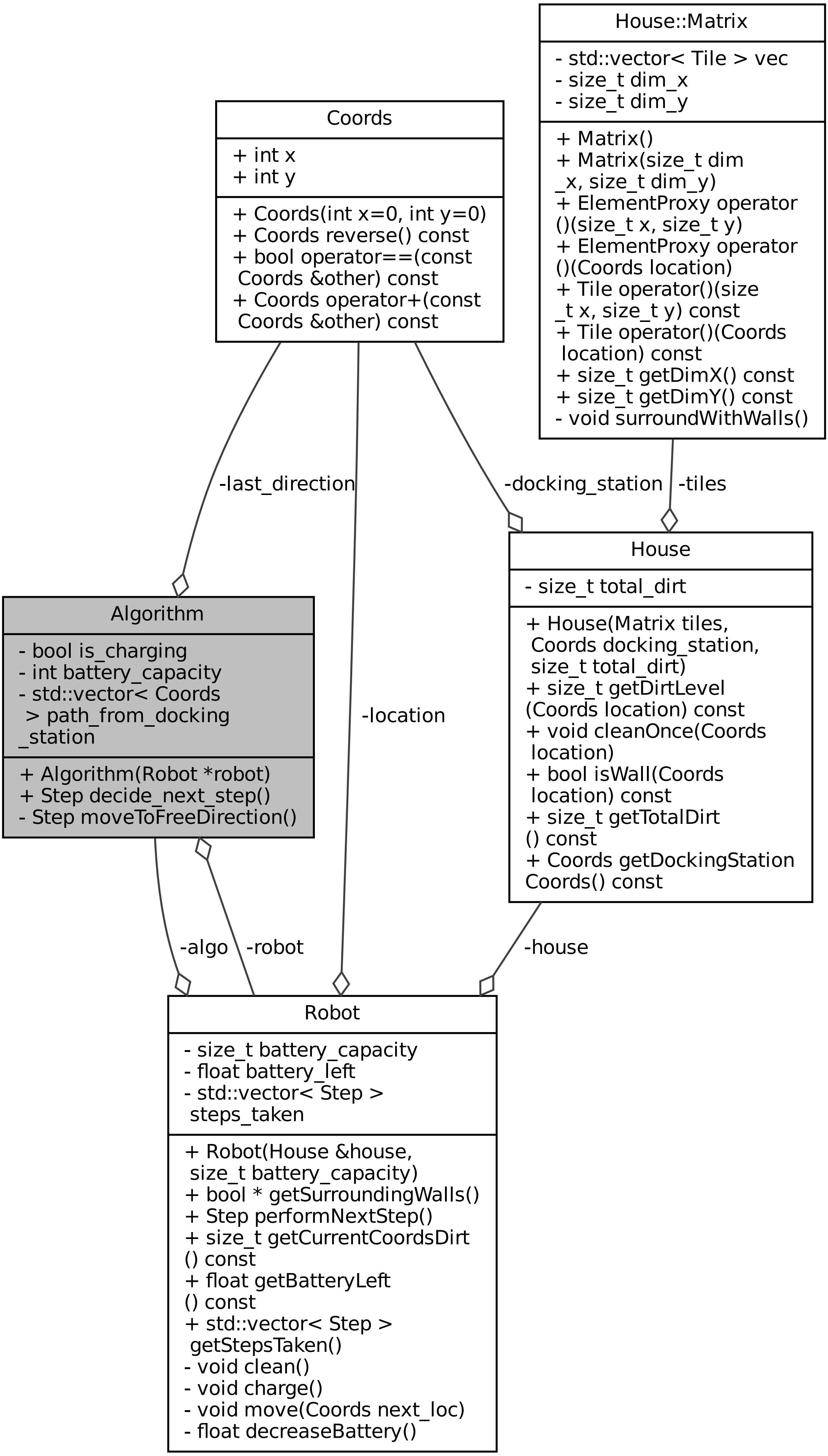
House::Matrix
- std::vector< Tile > vec
- size_t dim_x
- size_t dim_y
+ Matrix()
+ Matrix(size_t dim _x, size_t dim_y)
+ ElementProxy operator ()(size_t x, size_t y)
+ ElementProxy operator ()(Coords location)
+ Tile operator()(size _t x, size_t y) const
+ Tile operator()(Coords location) const
+ size_t getDimX() const
+ size_t getDimY() const
- void surroundWithWalls()
Coords
+ int x
+ int y
+ Coords(int x=0, int y=0)
+ Coords reverse() const
+ bool operator==(const Coords &other) const
+ Coords operator+(const Coords &other) const
-last_direction
-location
-docking_station
-tiles
House
- size_t total_dirt
+ House(Matrix tiles, Coords docking_station, size_t total_dirt)
+ size_t getDirtLevel (Coords location) const
+ void cleanOnce(Coords location)
+ bool isWall(Coords location) const
+ size_t getTotalDirt () const
+ Coords getDockingStation Coords() const
Algorithm
- bool is_charging
- int battery_capacity
- std::vector< Coords > path_from_docking _station
+ Algorithm(Robot *robot)
+ Step decide_next_step()
- Step moveToFreeDirection()
-algo
-robot
-house
Robot
- size_t battery_capacity
- float battery_left
- std::vector< Step > steps_taken
+ Robot(House &house, size_t battery_capacity)
+ bool * getSurroundingWalls()
+ Step performNextStep()
+ size_t getCurrentCoordsDirt () const
+ float getBatteryLeft () const
+ std::vector< Step > getStepsTaken()
- void clean()
- void charge()
- void move(Coords next_loc)
- float decreaseBattery()