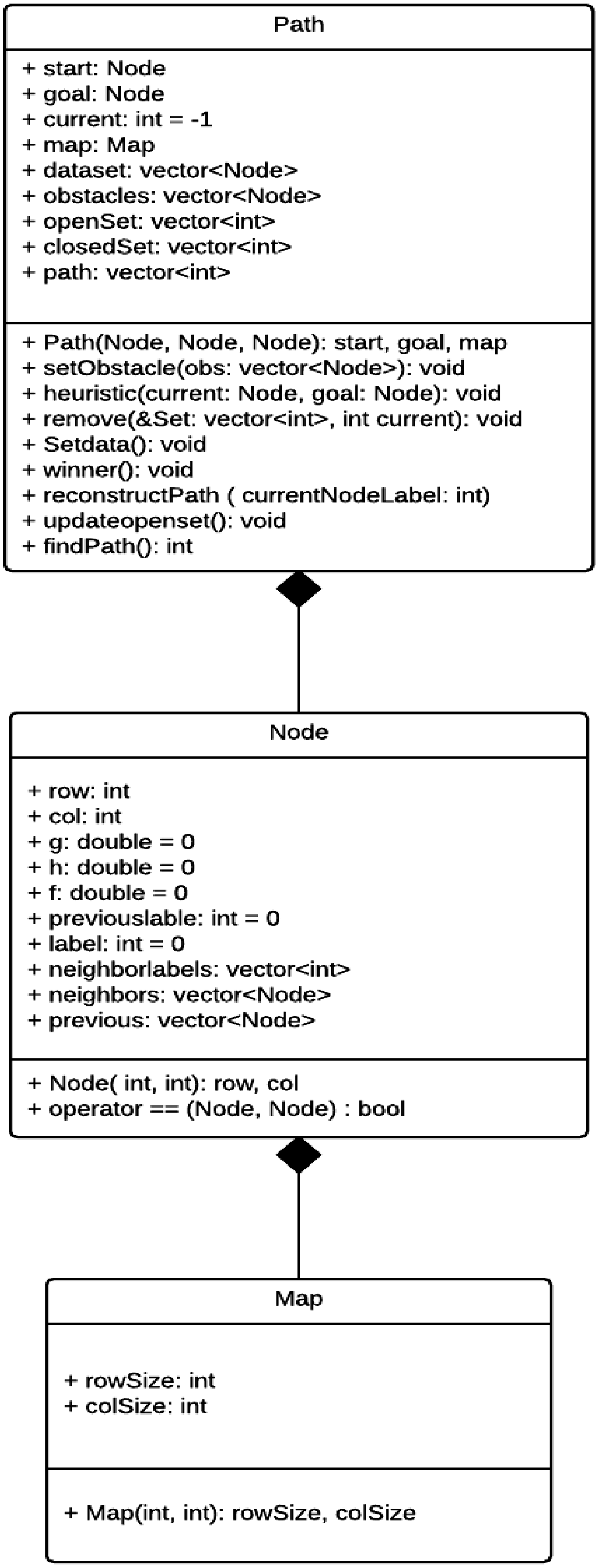

Path
+ start: Node
+ goal: Node
+ current: int = -1
+ map: Map
+ dataset: vector<Node>
+ obstacles: vector<Node>
+ openSet: vector<int>
+ closedSet: vector<int>
+ path: vector<int>
+ Path(Node, Node, Node): start, goal, map
+ setObstacle(obs: vector<Node>): void
+ heuristic(current: Node, goal: Node): void
+ remove(&Set: vector<int>, int current): void
+ Setdata(): void
+ winner(): void
+ reconstructPath (currentNodeLabel: int)
+ updateopenset(): void
+ findPath(): int
Node
+ row: int
+ col: int
+ g: double = 0
+ h: double = 0
+ f: double = 0
+ previouslable: int = 0
+ label: int = 0
+ neighborlabels: vector<int>
+ neighbors: vector<Node>
+ previous: vector<Node>
+ Node(int, int): row, col
+ operator == (Node, Node) : bool
Map
+ rowSize: int
+ colSize: int
+ Map(int, int): rowSize, colSize