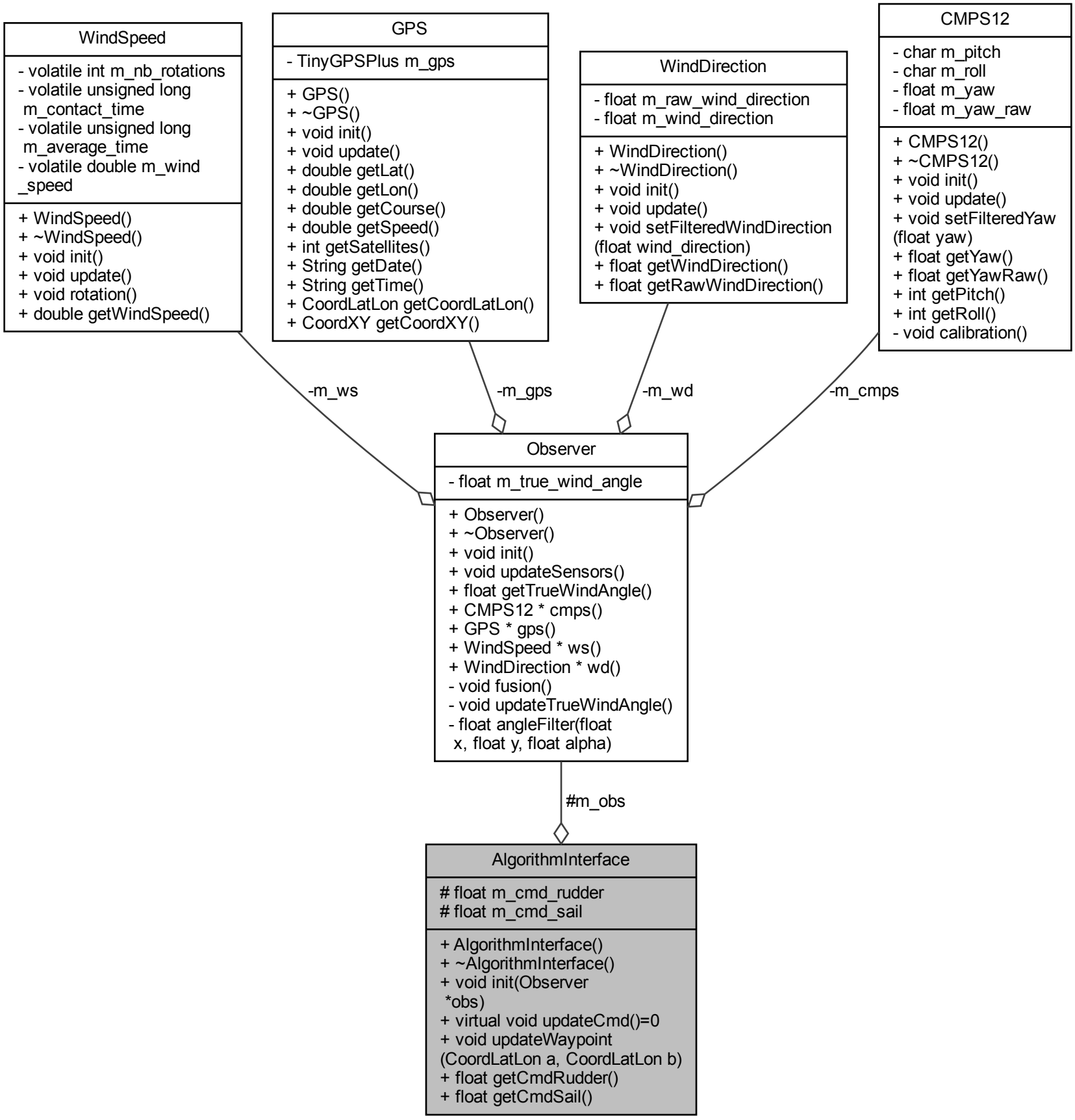
WindSpeed
- volatile int m_nb_rotations
- volatile unsigned long m_contact_time
- volatile unsigned long m_average_time
- volatile double m_wind_speed
+ WindSpeed()
+ ~WindSpeed()
+ void init()
+ void update()
+ void rotation()
+ double getWindSpeed()
GPS
- TinyGPSPlus m_gps
+ GPS()
+ ~GPS()
+ void init()
+ void update()
+ double getLat()
+ double getLon()
+ double getCourse()
+ double getSpeed()
+ int getSatellites()
+ String getDate()
+ String getTime()
+ CoordLatLon getCoordLatLon()
+ CoordXY getCoordXY()
WindDirection
- float m_raw_wind_direction
- float m_wind_direction
+ WindDirection()
+ ~WindDirection()
+ void init()
+ void update()
+ void setFilteredWindDirection (float wind_direction)
+ float getWindDirection()
+ float getRawWindDirection()
CMPS12
- char m_pitch
- char m_roll
- float m_yaw
- float m_yaw_raw
+ CMPS12()
+ ~CMPS12()
+ void init()
+ void update()
+ void setFilteredYaw (float yaw)
+ float getYaw()
+ float getYawRaw()
+ int getPitch()
+ int getRoll()
- void calibration()
-m_ws
-m_gps
-m_wd
-m_cmps
Observer
- float m_true_wind_angle
+ Observer()
+ ~Observer()
+ void init()
+ void updateSensors()
+ float getTrueWindAngle()
+ CMPS12 * cmps()
+ GPS * gps()
+ WindSpeed * ws()
+ WindDirection * wd()
- void fusion()
- void updateTrueWindAngle()
- float angleFilter(float x, float y, float alpha)
#m_obs
AlgorithmInterface
float m_cmd_rudder
float m_cmd_sail
+ AlgorithmInterface()
+ ~AlgorithmInterface()
+ void init(Observer *obs)
+ virtual void updateCmd()=0
+ void updateWaypoint (CoordLatLon a, CoordLatLon b)
+ float getCmdRudder()
+ float getCmdSail()