

#ifndef ${NAMESPACE}\_${NAME}\_H

#define ${NAMESPACE}\_${NAME}\_H

#include <iostream>

using namespace std;

${comment}

${includes}

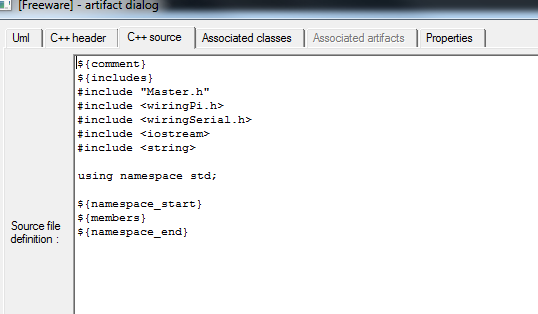
${declarations}

${namespace\_start}

${definition}

${namespace\_end}

#endif



${comment}

${includes}

#include "Master.h"

#include <wiringPi.h>

#include <wiringSerial.h>

#include <iostream>

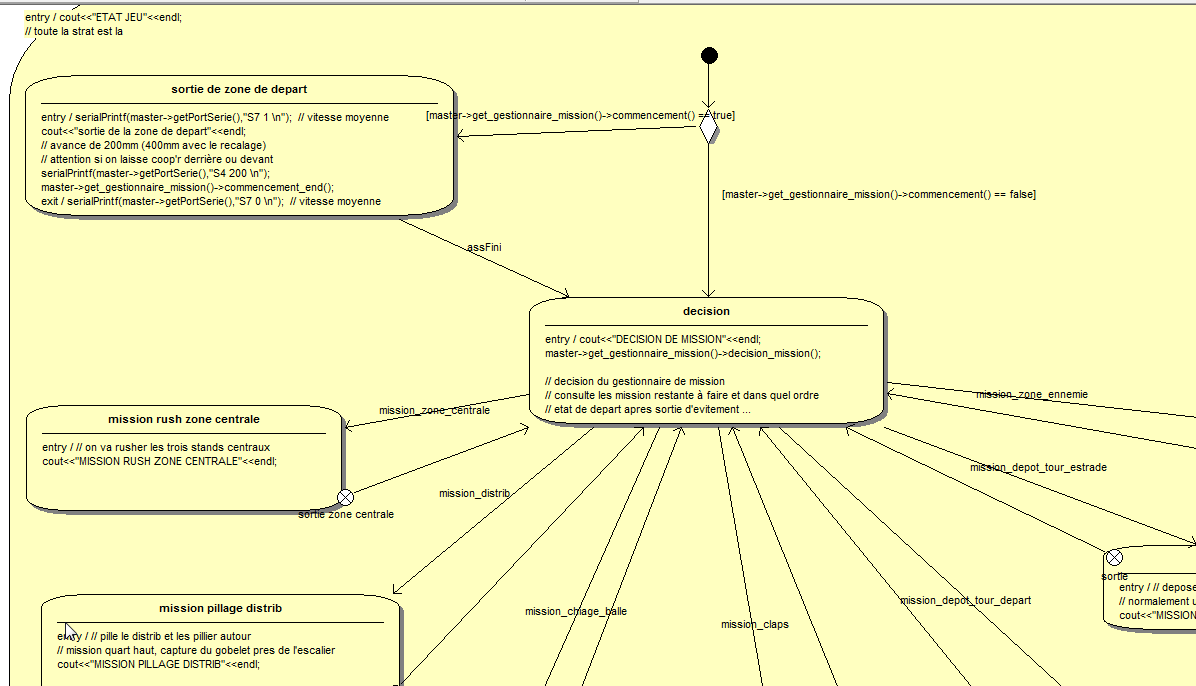
#include <string>

using namespace std;

${namespace\_start}

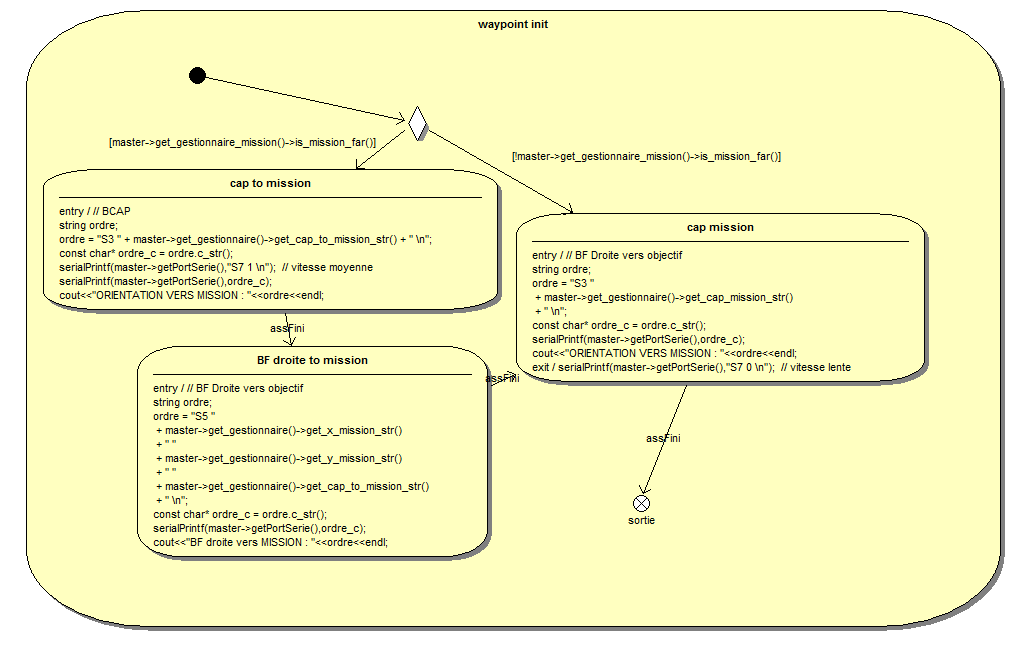
${members}

${namespace\_end}



cout<<"DECISION DE MISSION"<<endl;

master->get\_gestionnaire\_mission()->decision\_mission();



master->get\_gestionnaire\_mission()->is\_mission\_far()

cap to mission

// BCAP

string ordre;

ordre = "S3 " + master->get\_gestionnaire()->get\_cap\_to\_mission\_str() + " \n";

const char\* ordre\_c = ordre.c\_str();

serialPrintf(master->getPortSerie(),"S7 1 \n"); // vitesse moyenne

serialPrintf(master->getPortSerie(),ordre\_c);

cout<<"ORIENTATION VERS MISSION : "<<ordre<<endl;

// BF Droite vers objectif

string ordre;

ordre = "S5 "

+ master->get\_gestionnaire()->get\_x\_mission\_str()

+ " "

+ master->get\_gestionnaire()->get\_y\_mission\_str()

+ " "

+ master->get\_gestionnaire()->get\_cap\_to\_mission\_str()

+ " \n";

const char\* ordre\_c = ordre.c\_str();

serialPrintf(master->getPortSerie(),ordre\_c);

cout<<"BF droite vers MISSION : "<<ordre<<endl;

// BF Droite vers objectif

string ordre;

ordre = "S3 "

+ master->get\_gestionnaire()->get\_cap\_mission\_str()

+ " \n";

const char\* ordre\_c = ordre.c\_str();

serialPrintf(master->getPortSerie(),ordre\_c);

cout<<"ORIENTATION VERS MISSION : "<<ordre<<endl;

serialPrintf(master->getPortSerie(),"S7 0 \n"); // vitesse lente