



I Probe
probe()

Empty Probe
probe()

Normal Probe
x
y
width
height
grid
ScanAlong()

I Move
getAction()
getParameters()

I Simulation
loadConfiguration()
setRobot()
step()

Simulation
width
height
steps
Step()
printGrid()
listObjects()
printConfiguration()
landOnlyAdd in Sim()

I See
look()

Sight
width
height
direction
grid
direction

I Robot
get/move()

Search Robot
xLoc
yLoc
moves
direction
hasNext Moves
next Moves
previous Moves
map
get Move()
push Move Forward()
push Turn Right()
push Turn Left()
perform Action()
mark Map()
has Not Visited()
backTrack()