Obstacle

centroid

detected_dist()
pt_2_obst()

Robot

ctime : NoneType
eyed
k_mod
planning_process
rho : float
rtime : NoneType
sol : NoneType

set_option()

planning_process

Boundary

x_max
x_min
y_max
y_min

PolygonObstacle

bounding_circle_radius
centroid
x
y

plot()
pt_2_obst()

RoundObstacle

radius
x
y

plot()
pt_2_obst()

Process

name : str
pid

authkey()
daemon()
exitcode()
ident()
is_alive()
join()
name()
run()
start()
terminate()

RobotMsg

done_planning
intended_path_z1
intended_path_z2
latest_z

UnicycleKineModel

acc_max
l : int
q_dim : int
q_final
q_init
u_dim : int
u_final
u_init
u_max
z_dim : int
z_final
z_init

phi_0()
phi_1()
phi_2()
phi_3()

WorldSim

run()