**Obstacle**

centroid

detected_dist()
pt_2_obst()

**Robot**

ctime
eyed
k_mod
planning_process
rho : float
rtime
sol

set_option()

planning_process

**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()

**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**

pid

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

**RobotMsg**

done_planning
intended_path_z1
intended_path_z2
latest_z

**WorldSim**

run()