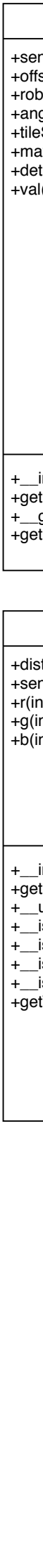


DistanceSensor

nsor(sensor)
set(int)
otDiameter(robotDiameter)
gle(sensorAngle)
Size(tileSize)
xDetect(float)
ectionLimit(detectionLimit)
(sensor)

nit__(self, sensor, sensorAngle, robotDiameter, tileSize, timeStep, detectionLimit=1): set
Distance(self): get
getAngle(self, globalRotation): get
GlobalDetection(self, globalRotation, robotPos): get

Gyroscope

+sensor(gyro)
+oldTime(float)
+index(index)

+__init__(self, gyro, index, timeStep): set
+def update(self, time, currentRotation): get

HeatSensor

+sensor(sensor)
+threshold(threshold)

+__init__(self, sensor, thershold, timeStep): set
+isClose(self): get

ColourSensor

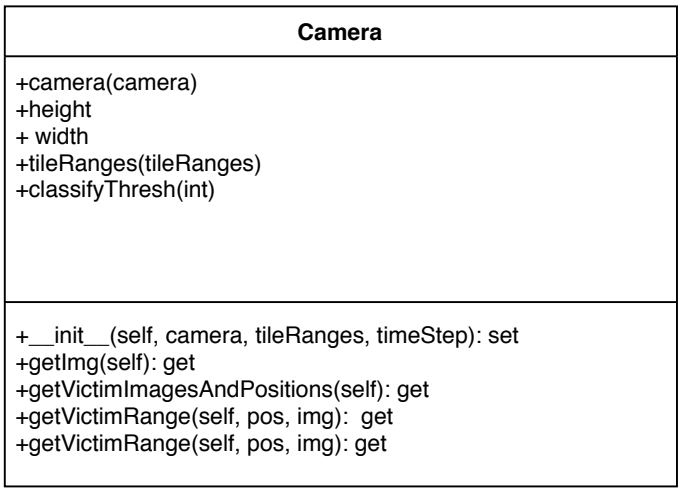
tance(self.distance = distancefromCenter)
nsor(sensor)
t)
nt)
nt)

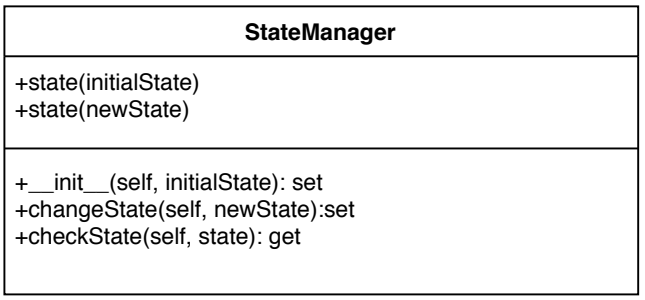
nit__(self, sensor, distancefromCenter, timeStep): set
Position(self, robotGlobalPosition, robotGlobalRotation): get
update(self): set
sTrap(self): get
sSwamp(self): get
sCheckpoint(self): get
sNormal(self): get
TileType(self): get

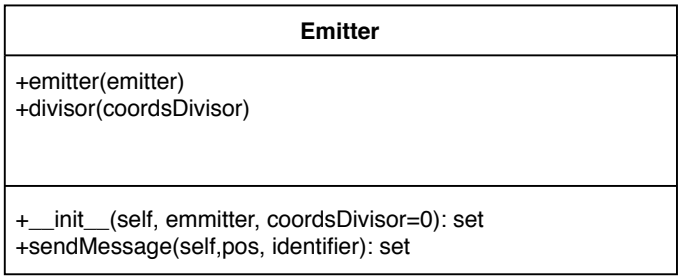
Gps

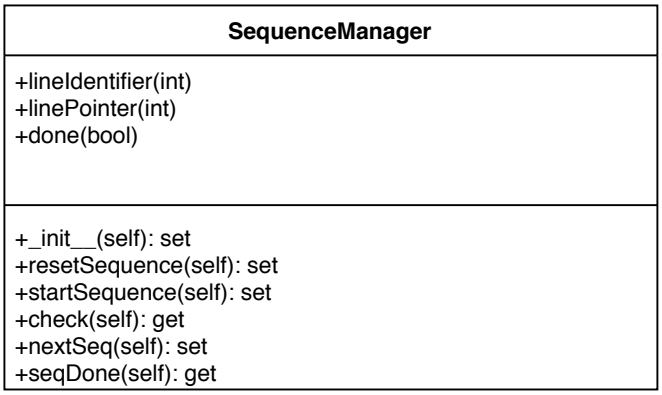
+gps(gps)
+multiplainer(coordsMultiplier)

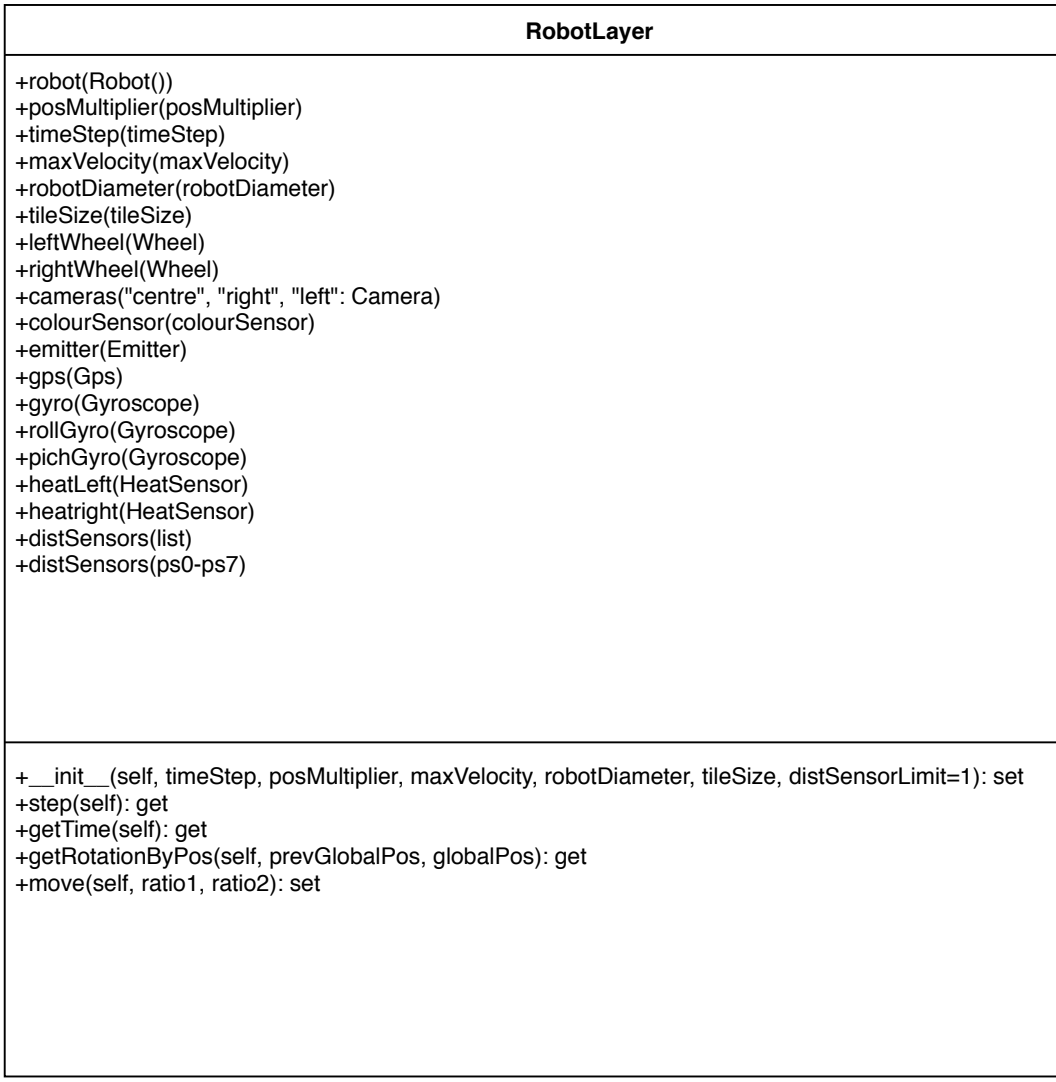
+__init__(self, gps,timeStep, coordsMultiplier=0): set
+getPosition(self): get


Camera
+camera(camera)
+height
+ width
+tileRanges(tileRanges)
+classifyThresh(int)
+__init__(self, camera, tileRanges, timeStep): set
+getImg(self): get
+getVictimImagesAndPositions(self): get
+getVictimRange(self, pos, img): get
+getVictimRange(self, pos, img): get


StateManager
+state(initialState)
+state(newState)
+__init__(self, initialState): set
+changeState(self, newState):set
+checkState(self, state): get


Emitter
+emitter(emitter)
+divisor(coordsDivisor)
+__init__(self, emmitter, coordsDivisor=0): set
+sendMessage(self,pos, identifier): set


SequenceManager
+lineIdentifier(int)
+linePointer(int)
+done(bool)
+_init__(self): set
+resetSequence(self): set
+startSequence(self): set
+check(self): get
+nextSeq(self): set
+seqDone(self): get


RobotLayer
+robot(Robot())
+posMultiplier(posMultiplier)
+timeStep(timeStep)
+maxVelocity(maxVelocity)
+robotDiameter(robotDiameter)
+tileSize(tileSize)
+leftWheel(Wheel)
+rightWheel(Wheel)
+cameras("centre", "right", "left": Camera)
+colourSensor(colourSensor)
+emitter(Emitter)
+gps(Gps)
+gyro(Gyroscope)
+rollGyro(Gyroscope)
+pichGyro(Gyroscope)
+heatLeft(HeatSensor)
+heatright(HeatSensor)
+distSensors(list)
+distSensors(ps0-ps7)
+__init__(self, timeStep, posMultiplier, maxVelocity, robotDiameter, tileSize, distSensorLimit=1): set
+step(self): get
+getTime(self): get
+getRotationByPos(self, prevGlobalPos, globalPos): get
+move(self, ratio1, ratio2): set