Pathfinding

SearchNode

N: SearchNode<N>

heuristic: double
cost: double
N: parentNode
location: JTS::Coordinate
goalsReached : Deque<PathfindingGoal>

PathfindingAlgorithm<N>

N: SearchNode<N>

+findPath(g:Graph<N> ,goal: N, start: N, goalThreshold: double, output: Deque<N>)

+findPath(g:Graph<N> ,goals: Deque<N>, start: N, goalThreshold: double): Deque<N>

Graph<N: SearchNode>

+ getNeighbouringNodes(node:N, goal:N, h: Heuristic<N>): List<N>

PathfindingHeuristic

<N: SearchNode<N>heuristic(a :N, b :PathfindingGoal) : double

PathfindingGoal

+getCoordinates()

SpatialHash

+getHash(point : JTS::Coordinate) : int