



RobotPositionManager.Robot
PositionManager

+ config_positions

+ nome_de_config_selecionada

+ FIELD_WIDTH

+ FIELD_HEIGHT

+ GRID_SCALE

+ MAX_JOGADORES

+ X_MIN

+ X_MAX

+ Y_MIN

+ Y_MAX

+ posicoes_atuais

+ marcadores_jogadores

+ tv_configs

+ canvas

+ canvas_height

+ canvas_width

+ on_double_click_in
_configs

+ click_on_grid

+ str CONFIG_POSITION_PATH

+ __init__(self)

+ criar_widgets(self)

+ None draw_player(self,
field_x, field_y)

+ click_on_grid(self,
tk.Event event)

+ None on_double_click
_in_configs(self, tk.Event
event)

+ None salvar_config
(self)

+ None clear_grid(self)

+ None nova_config(self)

+ None apagar_config
(self)

+ None update_table_config
(self)

+ destroy(self)

+ dict[str, list[tuple]] get_config_positions()

+ None save_config_positions
(dict[str, list[tuple]] dados)

tuple field_to_canvas
(self, float fx_, float fy_)

tuple canvas_to_field
(self, int cx, int cy)