SimmulationModule + Environment * environment + unsigned time Position + SimmulationModule() + void run() float x + void sendData() float y float z Object Environment + vector <Object *> objects + unsigned id + vector >Sensor Observer *> sensors + Vect3f position + Curve * curve

| + Environment() + void update() + vector <vect3f> getData()</vect3f> | + vector <sensorobserver *=""> * sensors + void update (unsigned time) + void notify () + void setObserver (vector <sensorobserver)< th=""><th></th></sensorobserver)<></sensorobserver> | |
|--|---|--|
| SensorObserver | Curve | |
| | | |

+ Curve()

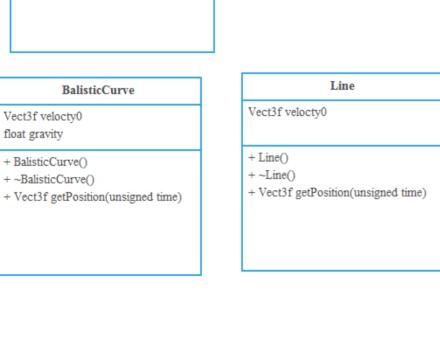
+ ~Curve()

+ SensorObserverImpl()

+ ~SensorObserverImpl()

+ ~SensorObserverImpl()

+ void update (Object *) + Vect3f makeNoise(Object *) + vector <Vect3f> getPositions()



| + Filter * filter; | | | | |
|--|--|--|--|--|
| | | | | |
| + FilterModule() | Track | | | |
| + void run() | unsigned id | | | |
| + void receiveData() | Vect3f current | | | |
| + void sendData() | Vect3f previous | | | |
| | Vect3f estimated | | | |
| | Parameters parameters | | | |
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| | | | | |
| KalmanFilter | | | | |
| Kamianritter | | | | |
| | Parameters | | | |
| vector <track *=""/> tracks | | | | |
| | | | | |
| + Filter() | | | | |
| + void estimate() | | | | |
| + vector <vect3f> getData()</vect3f> | | | | |
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| | | | | |
| ComparatorModule | PassedObject | | | |
| + vector <passedobject> original</passedobject> | unsigned id | | | |
| + vector <passedobject> filtered</passedobject> | Vect3f position | | | |
| . Total 4 assessorate lineses | veels1 position | | | |
| + ComparatorModule() | | | | |
| + void run() | | | | |
| + void receiveData() | | | | |
| + void sendData() | | | | |
| + compare() | | | | |
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| FilterError | | | | |
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| + float computeError (vector <passedob< td=""><td>ject>, vector <passedobject>)</passedobject></td></passedob<> | ject>, vector <passedobject>)</passedobject> | | | |
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| ConcreteError | | | | |
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| + float computeError (vector <passedobject>, vector <passedobject>)</passedobject></passedobject> | | | | |
| / A distribution / | | | | |
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FilterModule