Video

Image
- img: IplImage *
- date : long long

+ Image(IplImage *img)
+ ipl(): IplImage *
+ setIpl(IplImage *)
+ release()

SourceVideo
- mInfos: string

+ getInfos(): string
+ open()
+ close()
+ getFrame(Image &frame)

JpegImage
- cImg: cvMat *
- date: timespec *

+ JpegImage(Image *img)
+ setJpegImage(Image *img)
+ getcImg() : CvMat*
+ getDate(): long long

Camera
- mCapture: CvCapture *
- mIndice : int

+ camera(int index)
+ open(int index)

data

OrdreMouvement
+ direction: int
+ speed: int

+ getDirection(): int
+ getSpeed(): int
+ setDirection(int d)
+ setSpeed(int s)
+ OrdreMouvement(Message msg)

Position
- x: int
- y: int
- angle: int

+ getX(): int
+ getY(): int
+ getAngle(): int

image analyser

AnalyseImage
- imageFactor: int
- filterThreshold: int
- nbIterErode: int
- nbIterDilate: int
- robotHeihtReference: int
- robotWidthReference: int
- robotFactorReference: int

+ computePosition(Image *img): Position
+ computeAreaPosition(Image *img): Position

tools

ToolsTime
+ getTimeMillis(): long long

controler

monitor communication

Message
- dataType: char
- len: int
- data: char*

+ setMessage(char type, int len, char *data)
+ setInt(int value)
+ setChar(char c)
+ setString(const char* str)
+ setJpegImage(CompressedImage *cImg)
+ setPosition(Position p)

Server
- socketID: int
- active: bool

+ openServer(char * port)
+ getID(): int
+ closeServer()
+ send(Message *msg): int
+ receive(Message &msg): int
+ isActive(): bool

robot communication

CommunicationRobot
status: RobotStatus

+ RobotOpenCom(void) : RobotStatus
+ RobotCloseCom(void) : RobotStatus
+ RobotStart(void) : RobotStatus
+ RobotStop(void): RobotStatus
+ RobotSendChar(char c): RobotStatus
+ RobotGetChar(char *c): RobotStatus
+ RobotSetMotors(int motor_left, int motor_right): RobotStatus
+ RobotReloadWdt(void): RobotStatus
+ RobotGetSensor(int *sensor): RobotStatus
+ RobotGetOdo(int *odo_left, int *odo_right): RobotStatus
+ RobotGetVBat(int *vbat): RobotStatus