Astar Layoutnodes - startPoint:int - endpoint:int - nodeIndex:int - mapColumn:int - parentIndex:int - mapRow:int - rowIndex:int - openList : std::list<Layoutnodes> - columnIndex:int Мар - closedList : std::list<Layoutnodes> - heuristicCost:double - nodeList : std::vector<Layoutnodes> - pathCost:double - currentMap:std::vector<int> - neighbourNodes:vector<double> - totalCost:double - totalMap:int - path : std::list<Layoutnodes> - column:int + setNodeIndex(int, int, int):void - row:int + setParentIndex(int):void - moveDirection:int + getParentIndex(void):int + setHeuristicCost(double):void + displayMap(void):void + setStartPoint(int):void + storeMap(std::vector<int>):void + setPathCost(double):void + setEndPoint(int):void + setTotalCost(void):void + loadMap(void):void + calcPathCost(int):void + getMap(void):std::vector<int> + setCost(double):void + calcHeuristicCost(int, + deleteMap(void):void + output(void):void Layoutnodes):void + returnColumn(void):int + getCost(void):double + createNodeList(Map, int, int):void + getRowIndex(void):int + returnRow(void):int + planPath(void):void + getColumnIndex(void):int + setColumn(int):void + identifyNode(int, int):int + setRow(int):void + getIndex(void):int + inOpenList(int):bool + returnMap(void):std::vector<int> + double returnHCost(void):double + inClosedList(int):bool + returnDirection(void):int* + displayMap(void):void