

ObjectRef

+xpos: double
+ypos: double
+angle: double
+mass: double
+boundingRadius: double
+boundingRectangle[4][2]: double



SolidRef

RobotRef

+dx: double
+dy: double
+da: double
+sensors[]: SensorRef



SensorRef

+range: double
+aperture: double
+numRays: int
+rayWeights[]: double
+ypos: double
+ypos: double
+angle: double