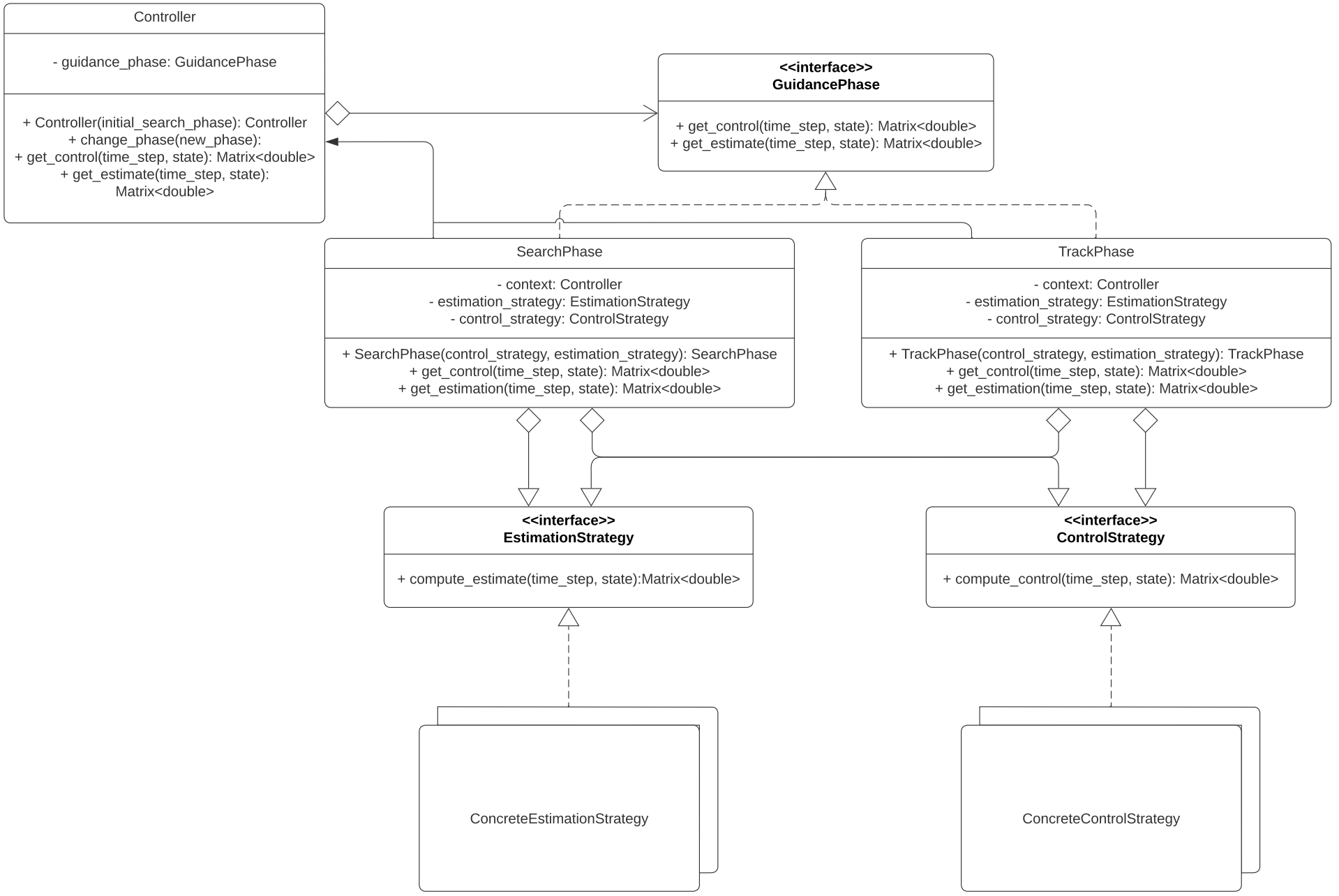
Controller
- guidance_phase: GuidancePhase
+ Controller(initial_search_phase): Controller
+ change_phase(new_phase):
+ get_control(time_step, state): Matrix<double>
+ get_estimate(time_step, state):
Matrix<double>
<<interface>>
GuidancePhase
+ get_control(time_step, state): Matrix<double>
+ get_estimate(time_step, state): Matrix<double>
SearchPhase
- context: Controller
- estimation_strategy: EstimationStrategy
- control_strategy: ControlStrategy
+ SearchPhase(control_strategy, estimation_strategy): SearchPhase
+ get_control(time_step, state): Matrix<double>
+ get_estimation(time_step, state): Matrix<double>
TrackPhase
- context: Controller
- estimation_strategy: EstimationStrategy
- control_strategy: ControlStrategy
+ TrackPhase(control_strategy, estimation_strategy): TrackPhase
+ get_control(time_step, state): Matrix<double>
+ get_estimation(time_step, state): Matrix<double>
<<interface>>
EstimationStrategy
+ compute_estimate(time_step, state):Matrix<double>
<<interface>>
ControlStrategy
+ compute_control(time_step, state): Matrix<double>
ConcreteEstimationStrategy
ConcreteControlStrategy