**class Domain Model**

```idlStruct``
sensor_plot_type
```
+ plot_id: plot_id_type [0..1]
+ position: position_coordinate_type
+ coordinate_specification: coordinate_specification_type
+ range_qualification: range_qualification_type [0..1]
+ azimuth_qualification: azimuth_qualification_type
+ elevation_qualification: elevation_qualification_type [0..1]
+ simulation_status: boolean
+ strength: plot_strength_type [0..1]
+ time_of_plot: time_type
+ additional_info: anonymous_blob_type
+ splash_spotting_area_id: splash_spotting_area_id_type [0..1]
+ jammer_indication: boolean

```idlStruct``
sensor_orientation_type
```
+ azimuth: azimuth_coordinate_type
+ elevation: elevation_coordinate_type [0..1]
+ time_of_validity: time_type
+ sensor_coordinate_system: coordinate_orientation_type

**unsigned short**
```
plot_strength_type
```

**unsigned long**
```
plot_id_type
```

**sd Basic Flow - Provide Sensor Orientation**

```idlInterface``
plot_reporting_sub
```

```idlInterface``
Provide_Sensor_Orientation_CMS
```

**loop**

[periodic]

write_sensor_orientation(sensor_orientation_type)

Sensor's with independent movement (e.g. surveillance and navigation radars that rotate) provide regular updates on its orientation. The frequency of updates is defined using the manage subsystem parameters use case.
activityFinal

Provide Subsystem Services
has successfully executed and
CMS has mastership

CMS

Manage Technical State

[Subsystem is ONLINE]
[Subsystem is ONLINE]
[Subsystem is not ONLINE]

Manage Tracking Zones
Manage Frequency Usage
Manage Transmission Sectors
Control Battle Override

Control Emissions

Provide Sensor Orientation

has executed and CMS has mastership

activityFinal