UML class

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agvs_controller (ROS Node)

number : int
state_sub :ros::Subscriber<const std_msgs::String>
station_sub : ros ::Subscriber<const std_msgs::String>
submit_shipment_scl : ros::ServiceClient<nist_gear::AGVToAssemblyStation>
curr_state : std::string
curr_station : std::string

state_callback(const std_msgs::String::ConstPtr& msg) : void
station_callback(const std_msgs::String::ConstPtr& msg) : void
+ submit_shipment(const std::string& assembly_station_name, const std::string& shipment_type) : bool

AGVToAssemblyStation

Request:
+ assembly_station_name :: std::string
+ shipment_type :: std::string

Response
+ success : bool
+ message : std::string

sensor_subcriber (ROS Node)

breakdownbeam0_sub : ros::Subscriber<const nist_gear::Proximity>
breakdownbeam0_change_sub : ros::Subscriber<const nist_gear::Proximity>
logical_camera_bins0_sub : ros::Subscriber<const nist_gear::LogicalCameraImage>
logical_camera_station2_sub : ros::Subscriber<const nist_gear::LogicalCameraImage>
proximity_sensor_0_sub : ros::Subscriber<const sensor_msgs::Range>
laser_profiler_0_sub : ros::Subscriber<const sensor_msgs::LaserScan>
quality_control_sensor_1_sub : ros::Subscriber<const nist_gear::LogicalCameraImage>
quality_control_sensor_2_sub : ros::Subscriber<const nist_gear::LogicalCameraImage>
quality_control_sensor_3_ sub : ros::Subscriber<const nist_gear::LogicalCameraImage>
quality_control_sensor_4_sub : ros::Subscriber<const nist_gear::LogicalCameraImage>
- n : ros::NodeHandle*

+ break_beam_callback(const nist_gear::Proximity::ConstPtr&) : void
+ break_beam_change_callback(const nist_gear::Proximity::ConstPtr&) : void
+ laser_profiler_callback(const sensor_msgs::LaserScan::ConstPtr&) : void
+ proximity_sensor_callback(const sensor_msgs::Range::ConstPtr&) : void
+ quality_callback1(const nist_gear::LogicalCameraImage::ConstPtr&) : void
+ quality_callback2(const nist_gear::LogicalCameraImage::ConstPtr&) : void
+ quality_callback3(const nist_gear::LogicalCameraImage::ConstPtr&) : void
+ quality_callback4(const nist_gear::LogicalCameraImage::ConstPtr&) : void
+ logical_camera_callback(const nist_gear::LogicalCameraImage::ConstPtr&) : void
+ logical_camera_callback2(const nist_gear::LogicalCameraImage::ConstPtr&) : void
+ startdetect() : void