rrtPlannerROS

+ width: int
+ height: int
+ mapSize: int
+ occupiedGridMap: bool*
+ originX: float
+ originY: float
+ resolution: float
+ step_size_: double
+ min_dist_from_robot_: double
+ initialized_: bool
+ costmap_ros_: costmap_2d::Costmap2DROS*
+ costmap_: costmap_2d::Costmap2D*

+ rrtPlannerROS()
+ ROSNodeHandle: ros::NodeHandle
+ initialize(): void
+ makePlan(): void
+ getCorrdinate(float&, float&): void
+ convertToCellIndex(float, float): int
+ convertToCoordinate(int, float&, float&): void
+ isCellInsideMap(float, float): bool
+ rrtPlanner(int, int): std::vector<int>
+ isStartAndGoalCellsValid(int, int): bool
+ isFree(int, int): bool
+ isFree(int): bool
+ GetRandomPoint(): std::pair<int, int>
+ getCellIndex(int, int): int
+ getCellRowID(int): int
+ getCellColID(int): int

vertex

- position: std::pair<float, float>
- idx: int
- parentIdx: int

+ getPosition()
+ getIdx()
+ getParentIdx()
+ setPosition()
+ setParentIdx()
+ setIdx()