

FinderBotsMaster

- timer_ : rclcpp::TimerBase::SharedPtr
- robots_ : std::vector<std::shared_ptr<FinderBots>>
- robot_count_ : int

- + FinderBotsMaster(robots: std::vector<std::shared_ptr<FinderBots>>, robot_count: int)
- + controlLoop() : void
- + initializeGoals(distance: double) : void

robots..*

FinderBots

- robot_name_ : std::string
- navigate_active_ : bool
- linear_speed_ : double
- goal_x_ : double
- goal_y_ : double
- obstacle_detected_ : bool
- move_flag_ : bool
- orientation_ : geometry_msgs::msg::Quaternion
- current_position_ : std::pair<double, double>

- + FinderBots(node_name: std::string, robot_name: std::string, navigate: bool, linear_vel: double)
- + setGoal(x: double, y: double) : void
- + odometryCallback(msg: nav_msgs::msg::Odometry::SharedPtr) : void
- + lidarCallback(msg: sensor_msgs::msg::LaserScan::SharedPtr) : void
- + imageCallback(msg: sensor_msgs::msg::Image::SharedPtr) : void
- + moveFlagCallback(msg: std_msgs::msg::Bool::SharedPtr) : void
- + navigationLoop() : void