Location

- n: NodeHandle
- vmarker_pub:Publisher
- sub: Subscriber
- odom_x:float
- odom_y:float
- stations: Stations
- stationMarkers: vector<Marker>

- odomCallback(const nav_msgs::Odometry::ConstPtr& msg):void
+ visualizeLocation(int argc, char** argv): int
+ displayStations(): int
+ publishStationLocations();int
+ isNearTarget(const visualization_msgs::Marker &target): bool
+ displayTargetLocation(visualization_msgs::Marker &dropoff): int
+ setMarkerProperties(int color, int id,Position p,
visualization_msgs::Marker &m):int
+<<constructor>> Location()