

# Localization\_module\_class\_diagram

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## Localization

- localizationPose: geometry\_msgs::PoseStamped
- entropy: double
- entropyThreshold: double
- mapPosePublisher: ros::Publisher
- rawPosePublisher: ros::Publisher
- localizationNode: ros::NodeHandle
- entropySubscriber: ros::Subscriber
- mapToBaseTfListen: tf::TransformListener
- EntropyCallback(std\_msgs::Float64::ConstPtr) : void
- GetRobotCoordinate(tf::StampedTransform) : void
- PublishMapPose() : void
- PublishRawPose() : void

- + initSubscribers(ros::Nodehandle) : void
- + SetEntropyThreshold(threshValue): bool
- + ExecuteLocalization(ros::NodeHandle) : void