

# 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(msg)
- GetRobotCoordinate(tf::StampedTransform)
- PublishMapPose()
- PublishRawPose()
- + SetEntropyThreshold(threshValue): bool
- + ExecuteLocalization()