

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(ros::NodeHandle)