```
+--------------------------------------------------------------+
|                   Package::seeker_swarm                      |
|                   Class : SwarmMaster                        |
+--------------------------------------------------------------+
| -timer_: rclcpp::TimerBase::SharedPtr                        |
| -publisher: rclcpp::Publisher<TWIST>::SharedPtr              |
| -robot_array: std::vector<std::shared_ptr<Robot»             |
| -nodes:int                                                   |
+--------------------------------------------------------------+
| + process_callback(): void                                   |
| + move(): void                                               |
+--------------------------------------------------------------+
```

uses

```
+-----------------------------------------------------------------------------------+
|                            Package::seeker_swarm                                   |
|                            Class : RobotSwarm                                      |
+-----------------------------------------------------------------------------------+
| -robot_name_curr: std::string                                                     |
| -navigate_curr:bool                                                                |
| -linear_speed_curr:double                                                          |
| -angular_speed_curr:double                                                         |
| -yaw_curr: double                                                                  |
| -roll_curr:double                                                                  |
| -pitch_curr: double                                                                |
| -goal_curr_x:double                                                                |
| -goal_curr_y:double                                                                |
| -m_distance_to_goal:double                                                         |
| -global_move_flag:bool                                                             |
| -obstacle:bool                                                                     |
| -callback_grp:rclcpp::CallbackGroup::SharedPtr                                     |
| -m_timer:rclcpp::TimerBase::SharedPtr                                              |
| -vel_publisher_curr: rclcpp::Publisher<geometry_msgs::msg::Twist>::SharedPtr       |
| -goal_pub :rclcpp::Publisher<std_msgs::msg::Bool>::SharedPtr                       |
| -robot_pose_curr: rclcpp::Subscription<nav_msgs::msg::Odometry>::SharedPtr         |
| -cam_sub_curr:rclcpp::Subscription<sensor_msgs::msg::Image>::SharedPtr             |
| -subscriber_move_flag:rclcpp::Subscription<std_msgs::msg::Bool>::SharedPtr         |
| -common_publisher_: rclcpp::Publisher<std_msgs::msg::Bool>::SharedPtr              |
| -lidar_sub_curr: rclcpp::Subscription<sensor_msgs::msg::LaserScan>::SharedPtr      |
| -curr_loc:std::pair<double, double>                                                |
| -navigate_curr_timer: rclcpp::TimerBase::SharedPtr                                 |
+-----------------------------------------------------------------------------------+
| + move_flag_callback(const std_msgs::msg::Bool::SharedPtr msg): void               |
| + set_goal(double x, double y): void                                              |
| + robot_pose_callback(const nav_msgs::msg::Odometry &msg): void                   |
| + normalize_angle_positive(double angle): double                                  |
| + lidar_callback(const sensor_msgs::msg::LaserScan& msg):void                     |
| + euclid_dist(): double                                                            |
| + yaw():double                                                                     |
| + angle_resize(double angle):double                                               |
| + move(double linear, double angular):void                                        |
| + stop():void                                                                      |
| + navigate_callback():void                                                         |
| + imageCallback(const sensor_msgs::msg::Image::SharedPtr msg): void                |
+-----------------------------------------------------------------------------------+
```