按代码写作的顺序：

1. 引用文件
2. 声明一个navigator的函数
3. 析构navigator的函数
4. Global位置的更新
5. Gps位置的更新
6. 传感器位置的更新
7. HOME点位置的更新
8. 飞行器状态的更新
9. 飞行器的地面检测函数
10. 飞行器的控制模式更新
11. 参数更新
12. task\_main\_trampoline的跳板函数
13. task\_main()函数
14. start()
15. status()
16. publish\_position\_setpoint\_triplet()
17. get\_default\_acceptance\_radius()
18. get\_acceptance\_radius()
19. get\_altitude\_acceptance\_radius()
20. get\_cruising\_speed()
21. get\_cruising\_throttle()
22. get\_acceptance\_radius()
23. add\_fence\_point()
24. load\_fence\_from\_file()
25. usage()
26. navigator\_main()
27. publish\_mission\_result()
28. publish\_geofence\_result()
29. publish\_att\_sp()
30. set\_mission\_failure(const char\* reason)

调用关系：

Check geofence violation

Gps\_pos

Sensor\_combined

Param\_update

Control\_mode

Vehicle\_status

Land\_detect

Home\_pos

Vehicle\_command

global\_pos

Global\_pos

Gps\_pos

Sensor\_combined

Vehicle\_status

Land\_detect

Control\_mode

Home\_pos

Onboard\_mission

Offboard\_mission

Param\_update

Vehicle\_command

更新topics

更新global\_pos和vehicle\_command

start

!thread\_should\_exit

订阅并更新 topics

Load geofence

Task\_main

Navigator\_main

fencefile

fence

stop

status

Task\_main\_trampoline

start