LawnMower

- path : string

+ mow() : void

NavigationUtils

- goal_position : vector<double>
- success_status : bool
- emergency_stop : bool
- + getCurrentLocation(): vector<double>
- + setDesiredPose(MoveBaseGoal&, vector<double>, Quaternion&): void
- + sendGoal(MoveBaseGoal&, SimpleActionClient<move_base_msgs::MoveBaseAction>&): void
- + convertToQuaternion(double) : Quaternion
- + checkGoalReach(SimpleActionClient <move_base_msgs::MoveBaseAction>&): bool
- + returnToHome(MoveBaseGoal&, SimpleActionClient<move_base_msgs::MoveBaseAction>&): bool
- + getPointsFromFile(std::string): vector<vector<double>>
- + emergencyStop(): bool

Note:

Defining the custom datatypes:

- ${\tt 1.\,MoveBaseGoal\ is\ of\ type\ move_base_msgs\ from\ move_base\ package}$
- 2. Quaternion is of type geometry_msgs
- 3. SimpleActionClient <move_base_msgs::MoveBaseAction> is part of the acitionlib package