AcmeExplorer

- nH: ros::NodeHandle
- botCheckFlag: bool

+ AcmeExplorer(std::string str): void
+ AcmeExplorer(): void
+ ~AcmeExplorer(): void
+ getbotCheckFlag(): bool
+ setbotCheckFlag(): void

Navigate

- navCheckFlag: bool
- obsDetectedFlag: bool
- velocityInput: geometry_msgs::Twist
- velLinear: double
- velAngular: double
- minDist: float
- scanData: float
- dist: float
- velPub: ros::Publisher
- scanSub: ros::Subscriber
- timer1: ros::Timer
- exploreFlag: bool
- count: int

+ Navigate(ros::NodeHandle& nh): void
+ ~Navigate(): void
+ setnavCheckFlag(): void
+ getnavCheckFlag(): bool
+ setobsDetectedFlag(): void
+ getobsDetectedFlag(): bool
+ explore(): void
+ moveForward(): void
+ turn(): void
+ scanCallBack(const sensor_msgs::LaserScan::ConstPtr& scan): void
+ obstacleDetected(): bool
+ getVelocity(): geometry_msgs::Twist
+ turnCallback(const ros::TimerEvent&): void

ViewImage

- camCheckFlag: bool
- imgReceivedFlag: bool
- picSavedFlag: bool
- imgSub: image_transport::Subscriber
- imgTitle: std::string
- service: ros::ServiceServer
- imagePtr: cv_bridge::CvImagePtr
- viewNh: ros::NodeHandle

+ ViewImage(): void
+ ~ViewImage(): void
+ getcamCheckFlag(): bool
+ setcamCheckFlag(): void
+ getimgReceivedFlag(): bool
+ setimgReceivedFlag(): void
+ getpicSavedFlag(): bool
+ setpicSavedFlag(): void
+ imageCallback(const sensor_msgs::ImageConstPtr& img): void
+ takePic(acme_explorer::Snap::Request &req, acme_explorer::Snap::Response &resp): bool
+ viewImg(): void