AcmeExplorer

- currentPose: std::vector<double>-
- botNh: ros::NodeHandle
- knownEnv: bool

+ AcmeExplorer(): void
+ ~AcmeExplorer(): void
+ getCurrentPose(): std::vector<double>
+ setCurrentPose(double x, double y, double theta): void

Navigate

- goalPose: std::vector<double>
- navNh: ros::NodeHandle
- velocity: geometry_msgs::Twist
- pubVelocity: ros::Publisher

+ Navigate(): void
+ ~Navigate(): void
+ getGoalPose(): std::vector<double>
+ setGoalPose(double x, double y, double theta): void
+ moveForward(): void
+ rotate(): void

Mapping

- mapNh: ros::NodeHandle
- generateMapClient: ros::ServiceClient

+ Mapping(): void
+ ~Mapping(): void
+ generateMap(): void
+ saveMap(): void

CaptureImg

- imgNh: ros::NodeHandle
- imgCaptureClient: ros::ServiceClient

+ CaptureImg(): void
+ ~CaptureImg(): void
+ capture(): void
+ saveImg(): void

AvoidObstacle

- obsNh: ros::NodeHandle
- minDist: double
- dist: double
- subScanner: ros::Subscriber

+ AvoidObstacle(): void
+ ~AvoidObstacle(): void
+ obsDetected(): bool
+ scannerCallback(sensor_msgs::LaserScan::ConstPtr& readings): void