

AcmeExplorer

- botNh: ros::NodeHandle
- currentPose: std::vector<double>
- goalPose: std::vector<double>
- velocity: geometry_msgs::Twist
- pubVelocity: ros::Publisher
- mapClient: ros::ServiceClient
- imgCaptureClient: ros::ServiceClient
- obstacleDist: double
- subScanner: ros::Subscriber

- + AcmeExplorer(): void
- + ~AcmeExplorer(): void
- + getCurrentPose(): std::vector<double>
- + setCurrentPose(double x, double y, double theta): void
- + getGoalPose(): std::vector<double>
- + setGoalPose(double x, double y, double theta): void
- + moveForward(): void
- + rotate(): void
- + generateMap(): void
- + saveMap(): void
- + captureImg(): void
- + saveImg(): void
- + obsDetected(): bool
- + scannerCallback(sensor_msgs::LaserScan::ConstPtr& readings): void