

TurtlebotMover

- + velMsg: geometry_msgs::Twist
- + nh: ros::NodeHandle
- + pubVel: ros::Publisher
- + subLaserScanner: ros::Subscriber
- + isObstacle: bool
- + obstacleThresh: double
- + newDirection: std::string

- + TurtlebotMover()
- + scanEnvCallback(const sensor_msgs::LaserScan::ConstPtr& msg): void
- + checkObstacle(): bool
- + setObstacle(bool obstacle): void
- + changeDirection(std::string newDirection): void
- + moveRobot(): void



AnomalyDetector

- + nh_: ros::NodeHandle
- + imgSub_: ros::Subscriber
- + pub_: ros::Publisher
- + cvImg_, maskImg_: cv::Mat
- + imgCoords_: cv::Point2i
- + worldCoords_: cv::Point3f
- + P_: cv::Matx34f
- + anomalyDetected_: bool

- + AnomalyDetector(const cv::Matx34f&, const cv::Matx34f&)
- + imgCallback(const sensor_msgs::Image::ConstPtr& msg): void
- + detectAnomaly(cv::Mat): cv::Point2i
- + localizePoints(cv::Point2i): cv::Point3f