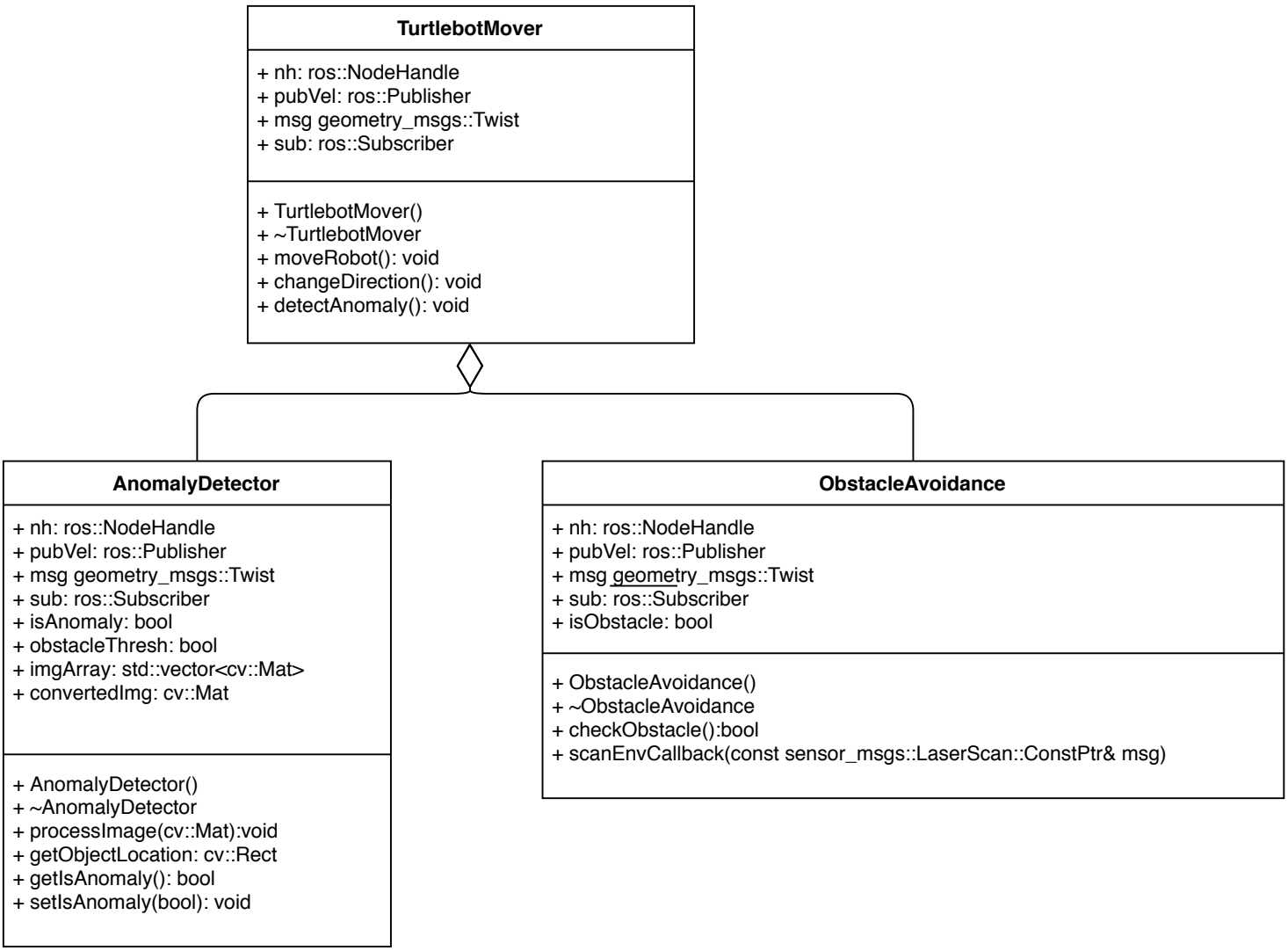
TurtlebotMover
+ nh: ros::NodeHandle
+ pubVel: ros::Publisher
+ msg geometry_msgs::Twist
+ sub: ros::Subscriber
+ TurtlebotMover()
+ ~TurtlebotMover
+ moveRobot(): void
+ changeDirection(): void
+ detectAnomaly(): void
AnomalyDetector
+ nh: ros::NodeHandle
+ pubVel: ros::Publisher
+ msg geometry_msgs::Twist
+ sub: ros::Subscriber
+ isAnomaly: bool
+ obstacleThresh: bool
+ imgArray: std::vector<cv::Mat>
+ convertedImg: cv::Mat
+ AnomalyDetector()
+ ~AnomalyDetector
+ processImage(cv::Mat):void
+ getObjectLocation: cv::Rect
+ getIsAnomaly(): bool
+ setIsAnomaly(bool): void
ObstacleAvoidance
+ nh: ros::NodeHandle
+ pubVel: ros::Publisher
+ msg geometry_msgs::Twist
+ sub: ros::Subscriber
+ isObstacle: bool
+ ObstacleAvoidance()
+ ~ObstacleAvoidance
+ checkObstacle():bool
+ scanEnvCallback(const sensor_msgs::LaserScan::ConstPtr& msg)