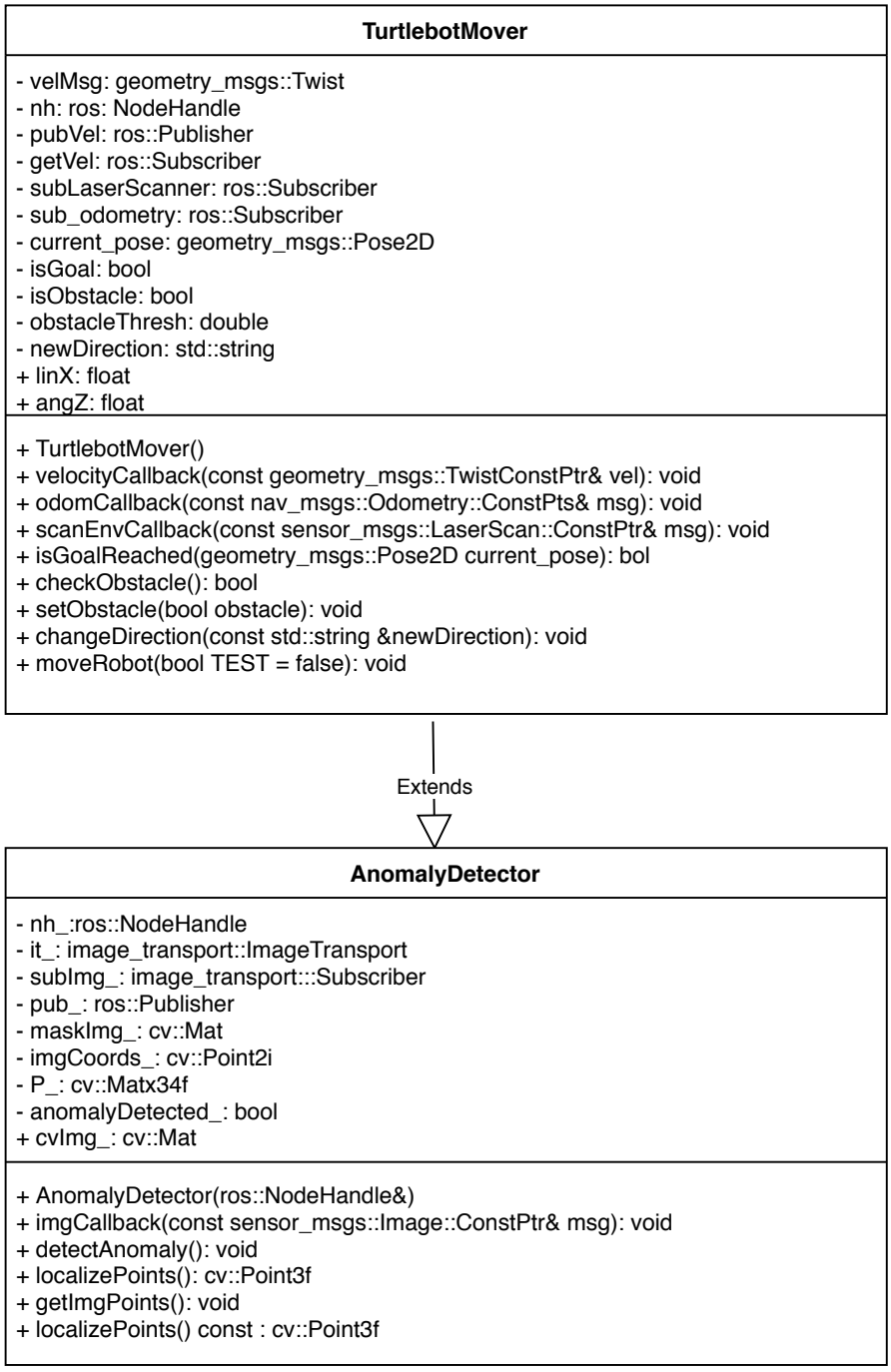
TurtlebotMover
- velMsg: geometry_msgs::Twist
- nh: ros: NodeHandle
- pubVel: ros::Publisher
- getVel: ros::Subscriber
- subLaserScanner: ros::Subscriber
- sub_odometry: ros::Subscriber
- current_pose: geometry_msgs::Pose2D
- isGoal: bool
- isObstacle: bool
- obstacleThresh: double
- newDirection: std::string
+ linX: float
+ angZ: float
+ TurtlebotMover()
+ velocityCallback(const geometry_msgs::TwistConstPtr& vel): void
+ odomCallback(const nav_msgs::Odometry::ConstPts& msg): void
+ scanEnvCallback(const sensor_msgs::LaserScan::ConstPtr& msg): void
+ isGoalReached(geometry_msgs::Pose2D current_pose): bol
+ checkObstacle(): bool
+ setObstacle(bool obstacle): void
+ changeDirection(const std::string &newDirection): void
+ moveRobot(bool TEST = false): void
Extends
AnomalyDetector
- nh_:ros::NodeHandle
- it_: image_transport::ImageTransport
- subImg_: image_transport:::Subscriber
- pub_: ros::Publisher
- maskImg_: cv::Mat
- imgCoords_: cv::Point2i
- P_: cv::Matx34f
- anomalyDetected_: bool
+ cvImg_: cv::Mat
+ AnomalyDetector(ros::NodeHandle&)
+ imgCallback(const sensor_msgs::Image::ConstPtr& msg): void
+ detectAnomaly(): void
+ localizePoints(): cv::Point3f
+ getImgPoints(): void
+ localizePoints() const : cv::Point3f