TurtleBa

- nh: ros::NodeHandle
- publishVelocity: ros::Publisher
- subscribeSensor: ros::Subscriber
- msg: geometry_msgs::Twist
- obstacleCheck: bool

+ TurtleBa()
+ sensorCallback(const sensor_msgs::LaserScan::ConstPtr&)
+ isObstacle() : bool
+ runAlgorithm()
+ ~TurtleBa()