ObstacleDetector

node : ros::NodeHandle()sub : ros::Subscriber()distSub : ros::Subscriber()distPub : ros::Publisher()

-isCollision : bool

+ ~ObstacleDetector() : void

+ ObstacleDetector(): void

+ laserCallback(const sensor_msgs::LaserScan::ConstPtr &distance) : void

+ distCallback(const std_msgs::Float64::ConstPtr& data) : void

+ getIsCollision(): bool

+ setIsCollision(bool collisionVal) : void

Navigation

- ObstacleDetector obstacle

- nh : ros::NodeHandle()

- msg : geometry msgs::Twist

pubNav : ros::Publisher()

+ Navigation(): void

+ ~Navigation() : void

+ move(bool detect):void