UML Class Diagram "*TinyNomad*"

Navigation

- n : ros::NodeHandle;
- obstacleRange : float;
- drivePower : geometry_msgs;

+ moveCommand : geometry_msgs::Twist;
+ turnCommand : geometry_msgs::Twist;
+ lasercallback : void;
+ getObstacleRange : float;

Vision

- counter : int;

+ cameraCallback : void;

Turtlebot

- nomad : Navigation::Navigation();
- n : ros::NodeHandle;
- velPub : ros::Publisher;
- laserData : ros::Subscriber;
- camera : Vision::Vision();
- cameraData : ros::Subscriber;

+ drive : int;