explorer.cpp

-nh_: ros::NodeHandle
-grid_: std::vector<vector<int4d>>
-laser_scan_: LaserScan
-server_: ros::ServiceServer

+constructor Mapper(void): void
+destructor ~Mapper(void): void
+serviceFunction(void): void

astar_navigator.cpp

-open_list_: std::vector
-closed_list_: std::vector
-row: std::double
-col: std::double
-dest: std::vector
-source: std::vector

+constructor navigator(void): void
+destructor ~navigator(void): void
+astar(vector<vector<int4d>>): vector