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<double>

-closed_list_: std::vector<double>

-row: double -col: double

-dest: std::vector<double>

-source: std::vector<double>

+constructor astar navigator(void): void

+destructor ~astar_navigator(void): void

+astar(vector<vector<int4d>>): vector