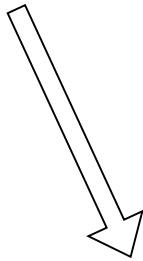


➡ **Rostopic**

→ **Class Member**

ROS:Start Point



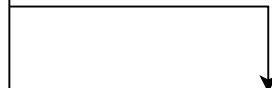
ROS:Goal Point



potential\_field\_node.cpp



<vector >obstacles  
-transformed start point  
-transformed goal point



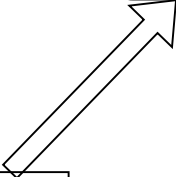
potential\_field  
.cpp



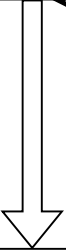
<vector> Path



ROS:Map



ROS:Path



Map Server

