Navigator

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Navigator
- n_: ros::NodeHandle - subClosestObj_ : ros::Subscriber - clientDelObj_ : ros::ServiceClient - clientGetPos_ : ros::ServiceClient - closestObject : std::string + closestPose: pacman::ObjPose + navStackStatus: bool + allowImgCallback: bool + sendGoal: bool + movement: std::shared_ptr<Movement>
+ Navigator() + laserScanCallback(const sensor_msgs::LaserScan::ConstPtr&) + imgCallback(const pacman::VecPoses::ConstPtr&) + closestCallback(const gazebo_msgs::ModelStates) + isNan(float) : static bool + checkVisuals() : bool + goalDelete()