

# Navigator

Ari Kupferberg | December 9, 2019

Navigator
<div><div>- n_ : ros::NodeHandle</div><div>- colObjPose_ :ros::Publisher</div><div>- subClosestObj_ :ros::Subscriber</div><div>- subClosestObj_ : ros::Subscriber</div><div>- clientDelObj_ : ros::ServiceClient</div><div>- clientGetPos_ : ros::ServiceClient</div><div>- closestObject : std::string</div><div>- deleteOkay : bool</div><div>- vels : geometry_msgs::Twist</div><div>- aclient : MoveBaseClient</div><div>+ closestPose: pacman::ObjPose</div><div>+ navStackStatus: bool</div><div>+ allowImgCallback: bool</div><div>+ sendGoal: bool</div><div>+ movement: std::shared_ptr&lt;Movement&gt;</div></div>
<div><div>+ Navigator()</div><div>+ laserScanCallback(const sensor_msgs::LaserScan::ConstPtr&amp;)</div><div>+ imgCallback(const pacman::VecPoses::ConstPtr&amp;)</div><div>+ closestCallback(const gazebo_msgs::ModelStates)</div><div>+ isNan(float) : static bool</div><div>+ checkVisuals() : bool</div><div>+ deleteObject() :</div><div>+ setDelete() :</div><div>+ resetDelete() :</div></div>