gas
+ gas() + startpoint: vector<double> + endpoint: vector<double> + aislelocations:vector<vector<double>> + currpos: vector<double> - nh: ros::NodeHandle - scansub : ros::Subscriber - velpub : ros::Publisher - move : geometry_msgs::Twist - dis_t: float - rot : float - vel : float - right : bool - left : bool + objectfound:bool + ~gas()
+ navigate(): void + collectobject():void + findobject():void + stoprobot():void + hasdestreached():bool + LaserCallback():void