

RobotController

- nodeHandler : ros::NodeHandle
- publishVelocity : ros::Publisher
- commandVelocity : geometry_msgs::Twist
- subscribeVelocity : ros::Subscriber

- + readVelocity() : void
- + writeVelocity : void
- + velocityCallback (const geometry_msgs::Twist::ConstPtr&) : void
- + getVelocity geometry_msgs::Twist