```
ld msg pose
+ robot x
+ robot y
+ robot th
+ seconds since epoch
+ server time
+ x recv time
+ y recv time
+ th recv time
+ time recv time
                -goal buf
              current pose
       cart status
- status
- no cart
- start dock
- current no arm
- current dock

    current goal

    current large point1

    current large point2

- current edge start
- no arm buf
and 7 more...
+ cart status()
+ ~cart status()
+ set status()
+ update current dock()
+ print_no_arm_list()
+ print dock list()
+ print_goal_list()
+ print_large_point1_list()
+ print_large_point2_list()
+ print edge start list()
and 14 more...
```