## MuskyNavPoint

- + std::string utm\_zone
- + double utm\_x
- + double utm\_y
- + geometry\_msgs::PointStamped map\_point
- + geometry\_msgs::PointStamped map\_next
- + bool last\_point
- + geometry\_msgs::PointStamped UTM\_input
- + utmMapGenerator(utm\_x, utm\_y, utm\_zone)
- + geometry\_msgs::PointStamped UTMtoMapPoint (UTM\_input)
- + move\_base\_msgs::MoveBaseGoal buildGoal (map\_point, map\_next, last\_point)

## MuskyNavGoal

- + int muskyid
- int location
- ros::NodeHandle n
- tf2::Quaternion my\_quat\_from\_euler
- bool client status
- bot std::string
- bool status
- + ros::Publisher VelocityPublisher
- + std::string concatMuskyId(int musky\_id)
- + MuskyNavGoal(ros::NodeHandle n,int musky\_id)
- + ~MuskyNavGoal()
- + void muskySendGoal(int musky\_id)