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)