

move base z client

robotBasePathPub

publishMessages

baseTrajectory

workingMode

+ OdomTracker()

+ setWorkingMode()

+ setPublishMessages()

pathStack

m mutex

+ pushPath()

+ setStartPoint() + getPath() # rtPublishPaths() # updateForward() # updateBackward()

+ popPath() + clearPath()

minPointDistanceBackward

subscribeToOdometryTopic

+ processOdometryMessage()

odomSub

Thresh

Thresh

Thresh