TURTLEBOT LAWN MOWER UML DIAGRAM

Gmapping

AMCL

Action lib

LawnMower

- pathXCoordinates : double [1..*]
- pathYCoordinates : double [1..*]
- pathAnglePose : double [1..*]

+ setPathX(double [1..*]) : void
+ setPathY(double [1..*]) : void
+ setAnglePose(double [1..*]) : void
+ setPoseGoals(double, double, geometry_msgs::Quaternion,
move_base_msgs::MovebaseGoal&) : double [1..*]
+ sendGoal(move_base_msgs::MoveBaseGoal,
actionlib::SimpleActionClient<move_base_msgs::MoveBaseAction>&) : void
+ quaternionCalculation(double) : tf::Quaternion
+ convertToQMsg(tf::Quaternion) : geometry_msgs::Quaternion
+ getPathXCoordinate( ) : const double [1..*] *
+ getPathYCoordinate( ) : const double[1..*] *
+ getPathAnglePose( ) : const double[1..*] *