UML Class Diagram

enigmaWalker

obstacle : bool

- msg : geometry msgs::Twist

vel : ros::Publisher scan : ros::Subscriber - minDistance : double

nh : ros::NodeHandle

+ enigmaWalker(): none

+ ~enigmaWalker(): none

+ getObstacle(): bool

+ scanCallback(const sensor msgs::LaserScan::ConstPtr&) : none

+ resetBot(): none + moveBot(): none