SmartAGV

- agvSub:ros::Subscriber
- agvPub:ros::Publisher
- agvServer:ros::ServiceServer
- action:Action
- nodeHandler:ros::NodeHandle

+ initialize(ros::NodeHandle &):void
- agvCallBack(const
std_msgs::String::ConstPtr&):void
- agvService(
agvbot::agvService::Request &,
agvbot::agvService::Response &):bool

Location

+ std::string loc;
+ double pointX;
+ double pointY;
+ double pointZ;
+ double orientationX;
+ double orientationY;
+ double orientationZ;
+ double orientationW;

+ Location(std::string, double, double,
double, double, double,
         double, double) : none

Action

- action:int
- nodeHandle : ros::NodeHandle
- naviCtrl : Navigation

+ Action():void
+ intialization(ros::NodeHandle &) : void
+ execute(int, const std::string &
args):void
- navigate(int, const std::string &
args):void

Navigation

- movebaseCmdVelPub : ros::Publisher
- mbClient:
actionlib::SimpleActionClient<move_base_msgs::MoveBaseAction>
- movebaseCmdVelPub:ros::Publisher

+ Navigation(void):void
+ initialize(ros::NodeHandler &):void
+ goTo(geometry_msg::Pose):void
+ abortMove(void):void
+ movebaseCallback(
const actionlib::SimpleClientGoalState&,
const move_base_msgs::MoveBaseResult::ConstPtr&
):void