smartAGV

- agvSub:ros::Subscriber
- agvPub:ros::Publisher
- agvServer:ros::ServiceServer
- action: Action
- nodeHandler:ros::NodeHandle
- + initialize(ros::NodeHandle &):void
- aqvCallBack(const

std msgs::String::ConstPtr&):void

- aqvService(

agvbot::agvService::Reguest &,

agvbot::agvService::Response &):bool



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