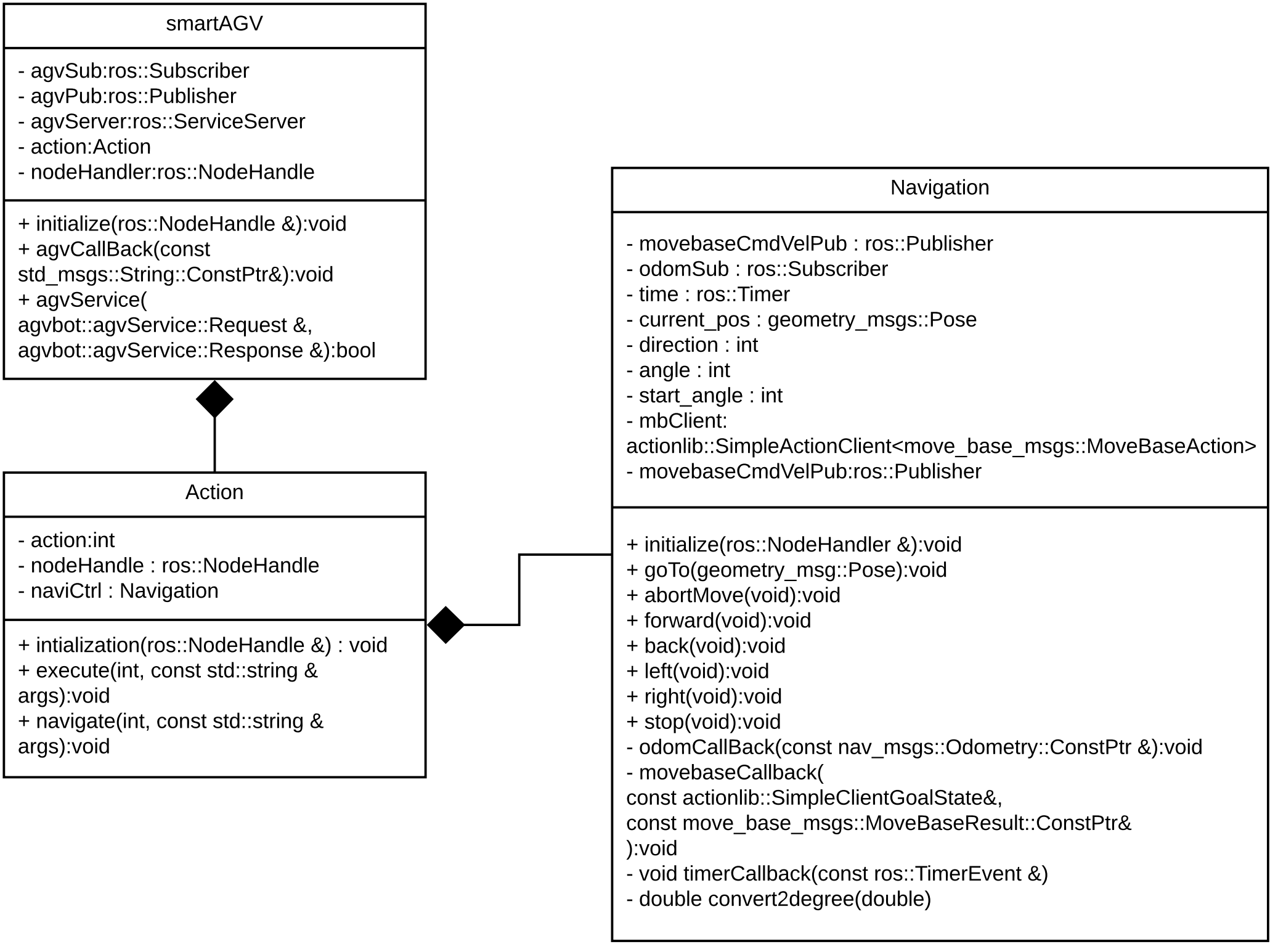
smartAGV
- agvSub:ros::Subscriber
- agvPub:ros::Publisher
- agvServer:ros::ServiceServer
- action:Action
- nodeHandler:ros::NodeHandle
+ initialize(ros::NodeHandle &):void
+ agvCallBack(const std_msgs::String::ConstPtr&):void
+ agvService(agvbot::agvService::Request &, agvbot::agvService::Response &):bool
Action
- action:int
- nodeHandle : ros::NodeHandle
- naviCtrl : Navigation
+ intialization(ros::NodeHandle &) : void
+ execute(int, const std::string & args):void
+ navigate(int, const std::string & args):void
Navigation
- movebaseCmdVelPub : ros::Publisher
- odomSub : ros::Subscriber
- time : ros::Timer
- current_pos : geometry_msgs::Pose
- direction : int
- angle : int
- start_angle : int
- mbClient: actionlib::SimpleActionClient<move_base_msgs::MoveBaseAction>
- movebaseCmdVelPub:ros::Publisher
+ initialize(ros::NodeHandler &):void
+ goTo(geometry_msg::Pose):void
+ abortMove(void):void
+ forward(void):void
+ back(void):void
+ left(void):void
+ right(void):void
+ stop(void):void
- odomCallBack(const nav_msgs::Odometry::ConstPtr &):void
- movebaseCallback(const actionlib::SimpleClientGoalState&, const move_base_msgs::MoveBaseResult::ConstPtr&):void
- void timerCallback(const ros::TimerEvent &)
- double convert2degree(double)