smartAGV

- agvSub:ros::Subscriber
- agvPub:ros::Publisher
- agvServer:ros::ServiceServer

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

Action

- action:int

+ setAction(int)
+ start()

Navigation

- current_pos:geometry_msgs::Pose
- goal:geometry_msgs::Pose
- mbClient:
actionlib::SimpleActionClient<move_base_msgs::MoveBaseAction>
- movebaseCmdVelPub:ros::Publisher

+ getLocation(void)
+ goTo(geometry_msgs::Pose)
+ stop()
+ abort()
+ resume()
- movebaseCallback(
const actionlib::SimpleClientGoalState&,
const move_base_msgs::MoveBaseResult::ConstPtr&
)