Name: Sarthak Mahajan UID: 115455177 Date: 12/07/18

## **frontierOps**

- occ threshold: int
- map open list: int
- map close list: int
- frontier open list: int
- frontier close list: int
- + frontierOps()
- + processFrontiers(const nav msgs::OccupancyGrid&, int, int, int): vector<vector<int>>
- + isFrontier(const nav msgs::OccupancyGrid&, int, int, int): bool
- + getAdjacentPts(int\*, int , int): void
- + getNearestFrontier(const sensor msgs::PointCloud): int
- + getFartherstFrontier(const sensor msgs::PointCloud): int
- + getDistance(float, float, float, float): float

## pathPlanner

- nh: ros::NodeHandle
- velPub: ros::Publisher
- msg: geometry msgs::Twist
- mapSub: ros::Subscriber
- frontierPtCloud: sensor msgs::PointCloud
- publisherPtCloud: ros::Publisher
- + pathPlanner()
- + fullScan(): void
- + mapCallback(const nav msgs::OccupancyGrid&): void
- + updateMap(): void
- + moveBot(const sensor msgs::PointCloud): void
- + getMedian(vector<int>): int