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pathPlanner

- currPos: float[2]
- finalPos: float[2]
- nh: ros::NodeHandle
- velPub: ros::Publisher
- msg: geometry_msgs::Twist

+ pathPlanner()
+ fullScan(): void
+ processFrontiers(): int
+ computePath(): int
+ moveRobot(): int

obsDetector

- collision: bool
- nh: ros::NodeHandle
- sub: ros::Subscriber

+ obsDetector()
+ checkObstacle(): bool
+ odCallback(): void

Mapper

- status: int
- nh: ros::NodeHandle

+ Mapper()
+ mapEnv(): void
+ exportMap(): int