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frontierOps

- frontierPtCloud: sensor_msgs::PointCloud
- publisherPtCloud: ros::Publisher

+ frontierOps()
+ isFrontier(): bool
+ getFrontierMedian(): int
+ getNearestFrontier(): int
+ getFartherstFrontier(): int

△

pathPlanner

- nh: ros::NodeHandle
- velPub: ros::Publisher
- msg: geometry_msgs::Twist
- mapSub: ros::Subscriber

+ pathPlanner()
+ fullScan(): void
+ processFrontiers(): int
+ mapCallback(): void
+ updateMap(): void
+ ~pathPlanner()