class huskyInspection

- nH : ros::NodeHandle
- cmd_vel : ros::Publisher
- message_ : geometry_msgs::Twist
- linear_velocity_ : double
- angular_velocity_ : double
- publisher_rate_ : const int

+ huskyInspection()
+ obstacleAvoid(pathPlan&) : bool
+ moveRobot(message_) : void
+ turnRobot(message_) : void
+ stopRobot(bool)
+ ~huskyInspection()

class pathPlan

- plan_success_ : bool
- collision_ : bool

+ pathPlan()
+ ~ pathPlan()
+ sensorCallback() : void
+ goalReached() : bool
+ generatePath() : bool

class detectObject

- image_ : cv::Mat
- dectected_ : bool
- count_ : int

+ getImage() : cv::Mat
+ getLocation() : double, double
+ findObject() : void