# path Namespace Reference

## Functions

def **send_goal** (**goal_pose**)
Function to send a goal to the move_base action server. More...

## Variables

**client** = actionlib.SimpleActionClient('move_base', MoveBaseAction)
Initialize action client for move_base. More...

**start_time** = rospy.get_time()

list **goals**
List of dictionaries representing goal poses. More...

**goal_pose** = PoseStamped()

**frame_id**

**x**

**y**

**z**

**w**

def **result** = **send_goal**(**goal_pose**)

**end_time** = rospy.get_time()

**elapsed_time** = **end_time** - **start_time**

## Function Documentation

### ◆ send_goal()

def path.send_goal ( goal_pose )

Function to send a goal to the move_base action server.

This function sends a desired pose to the move_base action server and waits for the result.

**Parameters**

**goal_pose** PoseStamped: The desired robot's goal pose.

**Returns**

int: The state of the action client after sending the goal, indicating success or failure.

```
Send a goal to move_base

Args:
goal_pose (PoseStamped): The desired robot's goal pose.

Returns:
int: succeeded or failed
```

## Variable Documentation

### ◆ client

path.client = actionlib.SimpleActionClient('move_base', MoveBaseAction)

Initialize action client for move_base.

### ◆ elapsed_time

path.elapsed_time = **end_time** - **start_time**

### ◆ end_time

path.end_time = rospy.get_time()

### ◆ frame_id

path.frame_id

### ◆ goal_pose

path.goal_pose = PoseStamped()

### ◆ goals

list path.goals

List of dictionaries representing goal poses.

Each dictionary contains 'x', 'y', 'z' coordinates and 'w' for orientation.

### ◆ result

def path.result = **send_goal**(**goal_pose**)

### ◆ start_time

path.start_time = rospy.get_time()

### ◆ w

path.w

### ◆ x

path.x

### ◆ y

path.y

### ◆ z

path.z

Generated by doxygen 1.8.13