The global\_planning algorithm function package is established by actionlib action communication mechanism. The algorithm package integrates three different algorithms, which can be selected according to the algorithm selection parameters in “alghrithom\_select. yaml”, and the different parameters of each algorithm can be adjusted to make the calculation path optimal.

The server can send path points information to publish to ROS, and save the path information to the specified folder (pose.csv) for the “follow\_waypoints” package to use, and print the running status of the path planner, algorithm details and path information to the terminal.

Note how to use feature packs：

1.Modify the file in alghrithom\_select.yaml according to the absolute path of each file on the PC.

2.Adjust the expansion coefficient in alghrithom\_select.yaml according to the needs of different map files, otherwise errors and abnormal waypoint information will sometimes occur.

Terminal display effect：





