

## nav2goal

```
-rclcpp::Publisher::SharedPtr pub2_  
-rclcpp_action::Client::SharedPtr action_client_  
-geometry_msgs::msg::PoseStamped goal_pose  
-geometry_msgs::msg::PoseWithCovarianceStamped  
initial_pose  
-rclcpp::Service::SharedPtr service_  
-std::shared_ptr service_response_  
-rclcpp::Client::SharedPtr delete_client_
```

```
+ClickedPointToPose(const std::string &name)  
+send_goal()  
+set_goal_pose(double box_x, double box_y)  
+set_initial_pose()  
+execute_next_task()
```