

From the package `example_ros_service`, modify the files `path_client.cpp` and `path_service2.cpp`. The client program should create a `Path` object that contains a sequence of poses to drive the robot to the upper-left corner of the maze.

The `path_service` should accept the entire sequence of poses and execute the sequence of subgoals to reach the final goal

Deliverables

- Your code, in package form, with `CMakeLists.txt`, `package.xml`, and source in a ROS package form **(Do NOT just submit the CPP file!)**
- A Kazaam movie (*.mp4) of your path service executing
- A brief report on your solution approach

Please ZIP all of these things up in a folder titled "ps3_caseID.zip" (ex. ps3_abc123.zip)