

PathPlanner

- goalMsg : move_base_msgs::MoveBaseActionGoal
- nodeHandler : ros::NodeHandle
- publishGoal : ros::Publisher
- readStatus : ros::Subscriber
- goalReached : int

- + setGoal(move_base_msgs::MoveBaseActionGoal) : void
- + getGoal() : move_base_msgs::MoveBaseActionGoal
- + sendGoal() : void
- + getStatus() : int
- + subscribeStatus() : void
- + reachedTargetCallback (const actionlib_msgs::GoalStatusArray::ConstPtr&) : void