PathPlanner

- goalMsg : move_base_msgs::MoveBaseActioGoal
- nodeHandler : ros::NodeHandle
- publishGoal : ros::Publisher
- readStatus : ros::Subscriber
- goalReached : int
- statusMessage ::actionlib_msgs::GoalStatusArray

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