
Algorithm nodeA_client

Function callback(msg)

Extract position and velocity information from Odometry message

Publish the extracted information to *"/pos_vel"* using PosVel custom message

end

Create the publisher for *"/pos_vel"* topic

Try

Initialize Ros Node

Subscribe to *"/odom"* topic using the defined **callback**

Create a SimpleActionClient for *"PlanningAction"*

Wait for the action server to start

Goal \leftarrow assignment_2_2023.msg.PlanningGoal()

while ros is running **do**

Prompt user to enter the goal position (x, y)

goal.target_pose.pose.position.x \leftarrow x

goal.target_pose.pose.position.y \leftarrow y

Send the goal to the action server

while the goal is not succeeded **do**

Ask to the user to cancel or not the goal

If 'c' is pressed

Cancel the goal

Break out of the loop

end

end

Except rospy.ROSInterruptException

Display an error message

end
