Working with ROS actionlib

⇒ On ROS services, the user implements a request/reply interaction between two nodes, but if the reply takes too much time or if

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the service is not finished with the work

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we have to ~~wright~~ wait until it completes, blocking the main application.

⇒ Actionlib package provides a standard way to implement these kind of Preemptive tasks.

⇒ Actionlib is highly used in robot arm navigation and mobile robot navigation.

⇒ The action specification is stored inside the action file having an extension of .action.

⇒ The action file has the following parts:

1) Goal ⇒ The action client can send a goal that has to be executed by the action server.

2) Feedback ⇒ Feedback is simply giving the progress of the current operation inside the callback function.

3) Result ⇒ After completing the goal, the action server will send a final result of completion

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{ It can be the computational result or an acknowledgment. }