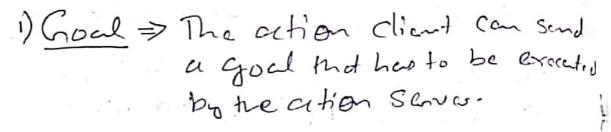
Working with ROS actionlib

a graquest/oneply interaction between two modes, but if the oneply takes too much time on a

the Service is not finiched with to

Completes, blocking the main application

- ETActionlib parkage provides a standard way to implement these kind of Preemptive tooks.
- => Actionlib is highly would in subst ann navigation and mobile subst navigation.
- => The action specification is stored inside the action file having an extension of action.
- => The action file has the following parts:



2) Faidbalk => Faidbalk is Simply Giving the progress of the current operation inside the Culbak furtion.

3) Result => After Completing the goal, the action server will send a find onesult of Completion

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At can be the Computational onesult on an alkno ledgment.

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