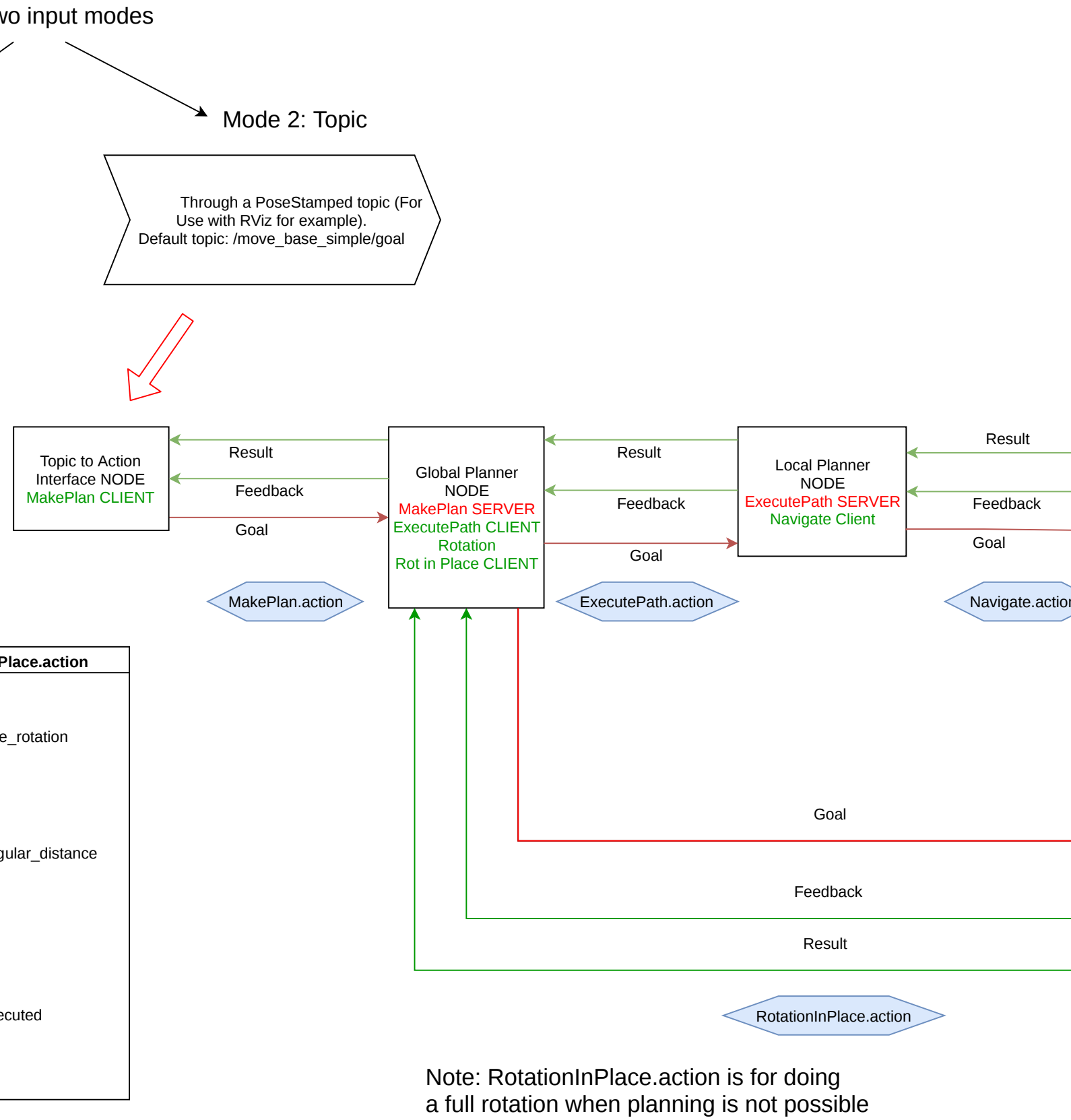
Tv

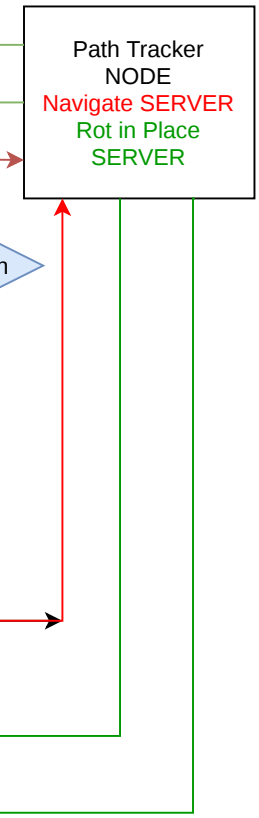
Mode 1: Mission

Load .yaml with list of goal poses and orientations
Procedure: To start the mission call
/mission_interface/start_mission
When a goal is reached, to continue to next goal call
/mission_interface/continue_mission
If you want to reload the mission data (not during the mission) call **/mission_interface/reload_mission_data**

Actions			
MakePlan.action	**ExecutePa**	**Navigate.action**	**RotationIn**
Goal **PoseStamped** global_goal *Feedback* **Float32** distance_to_goal **UInt8** global_waypoint **String** percent_achieved **String** ETA **Duration** travel_time *Result* **Bool** finished **Bool** not_possible **UInt8** times_replanned **UInt8** times_emergency_stop **Duration** time_spent	*Goal* **MultiDOFJointTrj** path *Feedback* **Float32** planning_rate **String** status **UInt8** global_waypoint *Result* **Bool** arrived	*Goal* *Feedback* **Distance To Goal** **Time Navigating** *Result* **Arrived or not** **Final Angle and Distance Difference**	*Goal* **Bool** execut *Feedback* **Float32** ang *Result* **Bool** exe



Note: RotationInPlace.action is for doing a full rotation when planning is not possible


Path Tracker
NODE
Navigate SERVER
Rot in Place
SERVER