

Mission Manager services

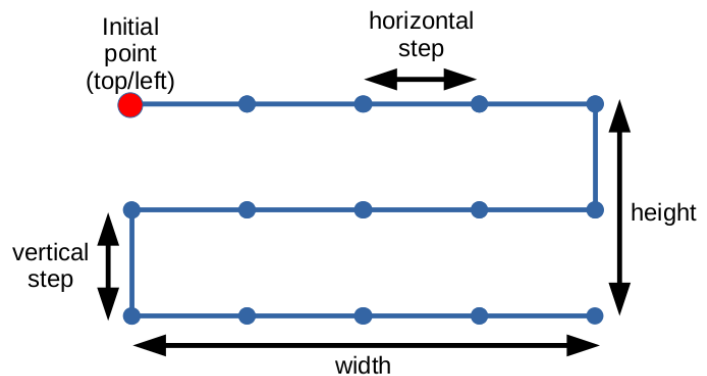
Start sweeping:

Name: /mission_manager/start_sweep

Description: it starts a new sweeping task with the specified dimensions. If “*wall_to_wall*” is set to true, the value for the “*width*” parameter is ignored.

Request:

- float64 width
- float64 height
- float64 horizontal_step
- float64 vertical_step
- bool wall_to_wall



Reply: empty

Stop sweeping

Name: /mission_manager/stop_sweep

Description: it stops the current sweeping task (if any).

Request: empty

Reply: empty

Pause sweeping

Name: /mission_manager/pause_sweep

Description: it pauses the current sweeping task (if any).

Request: empty

Reply: empty

Resume sweeping

Name: /mission_manager/resume_sweep

Description: it resumes the currently paused sweeping task (if any).

Request: empty

Reply: empty

Start vertical inspection

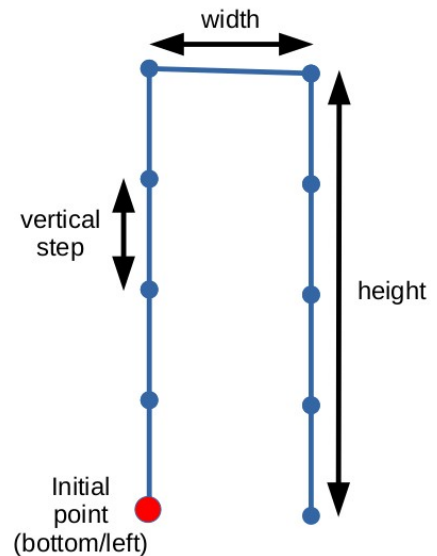
Name: /mission_manager/start_vertical_inspection

Description: it starts a new vertical inspection task with the specified dimensions. If “to_ceiling” is set to true, the value for the “height” parameter is ignored.

Request:

- float64 height
- float64 width
- float64 vertical_step
- bool to_ceiling

Reply: empty



Stop vertical inspection

Name: /mission_manager/stop_vertical_inspection

Description: it stops the current vertical inspection task (if any).

Request: empty

Reply: empty

Pause vertical inspection

Name: /mission_manager/pause_vertical_inspection

Description: it pauses the current vertical inspection task (if any).

Request: empty

Reply: empty

Resume vertical inspection

Name: /mission_manager/resume_vertical_inspection

Description: it resumes the currently paused vertical inspection task (if any).

Request: empty

Reply: empty

Hover

Name: /mission_manager/hover

Description: it makes the platform to keep its current position.

Request: empty

Reply: empty

Go home

Name: /mission_manager/go_home

Description: it makes the platform to go to the home position.

Request: empty

Reply: empty

Set home

Name: /mission_manager/set_home

Description: it overwrites the home position with the current vehicle X/Y coordinates (Z coordinate is not modified, set to 1.5 m by default).

Request: empty

Reply: empty

Save point

Name: /mission_manager/save_point

Description: it saves the current vehicle position (X/Y/Z coordinates) and labels it with the provided string. Saved positions are kept in four lists stored as ROS parameters *saved_positions/[x/y/z/description]*.

Request:

- string description

Reply:

- bool ok

Go to point

Name: /mission_manager/go_to_point

Description: it makes the platform to go the specified position.

Request:

- float64 x
- float64 y
- float64 z

Reply: empty