;; Auto-generated. Do not edit!

(when (boundp 'robotnik\_msgs\_new::BatteryDockingStatus)

(if (not (find-package "ROBOTNIK\_MSGS\_NEW"))

(make-package "ROBOTNIK\_MSGS\_NEW"))

(shadow 'BatteryDockingStatus (find-package "ROBOTNIK\_MSGS\_NEW")))

(unless (find-package "ROBOTNIK\_MSGS\_NEW::BATTERYDOCKINGSTATUS")

(make-package "ROBOTNIK\_MSGS\_NEW::BATTERYDOCKINGSTATUS"))

(in-package "ROS")

;;//! \htmlinclude BatteryDockingStatus.msg.html

(intern "\*MODE\_DISABLED\*" (find-package "ROBOTNIK\_MSGS\_NEW::BATTERYDOCKINGSTATUS"))

(shadow '\*MODE\_DISABLED\* (find-package "ROBOTNIK\_MSGS\_NEW::BATTERYDOCKINGSTATUS"))

(defconstant robotnik\_msgs\_new::BatteryDockingStatus::\*MODE\_DISABLED\* "disabled")

(intern "\*MODE\_AUTO\_HW\*" (find-package "ROBOTNIK\_MSGS\_NEW::BATTERYDOCKINGSTATUS"))

(shadow '\*MODE\_AUTO\_HW\* (find-package "ROBOTNIK\_MSGS\_NEW::BATTERYDOCKINGSTATUS"))

(defconstant robotnik\_msgs\_new::BatteryDockingStatus::\*MODE\_AUTO\_HW\* "automatic\_hw")

(intern "\*MODE\_AUTO\_SW\*" (find-package "ROBOTNIK\_MSGS\_NEW::BATTERYDOCKINGSTATUS"))

(shadow '\*MODE\_AUTO\_SW\* (find-package "ROBOTNIK\_MSGS\_NEW::BATTERYDOCKINGSTATUS"))

(defconstant robotnik\_msgs\_new::BatteryDockingStatus::\*MODE\_AUTO\_SW\* "automatic\_sw")

(intern "\*MODE\_MANUAL\_SW\*" (find-package "ROBOTNIK\_MSGS\_NEW::BATTERYDOCKINGSTATUS"))

(shadow '\*MODE\_MANUAL\_SW\* (find-package "ROBOTNIK\_MSGS\_NEW::BATTERYDOCKINGSTATUS"))

(defconstant robotnik\_msgs\_new::BatteryDockingStatus::\*MODE\_MANUAL\_SW\* "manual\_sw")

(defclass robotnik\_msgs\_new::BatteryDockingStatus

:super ros::object

:slots (\_operation\_mode \_contact\_relay\_status \_charger\_relay\_status ))

(defmethod robotnik\_msgs\_new::BatteryDockingStatus

(:init

(&key

((:operation\_mode \_\_operation\_mode) "")

((:contact\_relay\_status \_\_contact\_relay\_status) nil)

((:charger\_relay\_status \_\_charger\_relay\_status) nil)

)

(send-super :init)

(setq \_operation\_mode (string \_\_operation\_mode))

(setq \_contact\_relay\_status \_\_contact\_relay\_status)

(setq \_charger\_relay\_status \_\_charger\_relay\_status)

self)

(:operation\_mode

(&optional \_\_operation\_mode)

(if \_\_operation\_mode (setq \_operation\_mode \_\_operation\_mode)) \_operation\_mode)

(:contact\_relay\_status

(&optional \_\_contact\_relay\_status)

(if \_\_contact\_relay\_status (setq \_contact\_relay\_status \_\_contact\_relay\_status)) \_contact\_relay\_status)

(:charger\_relay\_status

(&optional \_\_charger\_relay\_status)

(if \_\_charger\_relay\_status (setq \_charger\_relay\_status \_\_charger\_relay\_status)) \_charger\_relay\_status)

(:serialization-length

()

(+

;; string \_operation\_mode

4 (length \_operation\_mode)

;; bool \_contact\_relay\_status

1

;; bool \_charger\_relay\_status

1

))

(:serialize

(&optional strm)

(let ((s (if strm strm

(make-string-output-stream (send self :serialization-length)))))

;; string \_operation\_mode

(write-long (length \_operation\_mode) s) (princ \_operation\_mode s)

;; bool \_contact\_relay\_status

(if \_contact\_relay\_status (write-byte -1 s) (write-byte 0 s))

;; bool \_charger\_relay\_status

(if \_charger\_relay\_status (write-byte -1 s) (write-byte 0 s))

;;

(if (null strm) (get-output-stream-string s))))

(:deserialize

(buf &optional (ptr- 0))

;; string \_operation\_mode

(let (n) (setq n (sys::peek buf ptr- :integer)) (incf ptr- 4) (setq \_operation\_mode (subseq buf ptr- (+ ptr- n))) (incf ptr- n))

;; bool \_contact\_relay\_status

(setq \_contact\_relay\_status (not (= 0 (sys::peek buf ptr- :char)))) (incf ptr- 1)

;; bool \_charger\_relay\_status

(setq \_charger\_relay\_status (not (= 0 (sys::peek buf ptr- :char)))) (incf ptr- 1)

;;

self)

)

(setf (get robotnik\_msgs\_new::BatteryDockingStatus :md5sum-) "d7c3a4e25e4a4a665c4a1dd0862edfc2")

(setf (get robotnik\_msgs\_new::BatteryDockingStatus :datatype-) "robotnik\_msgs\_new/BatteryDockingStatus")

(setf (get robotnik\_msgs\_new::BatteryDockingStatus :definition-)

"# Modes of operation:

# no docking station contacts

string MODE\_DISABLED=disabled

# Unattended relay detection & activation with no inputs/outputs feedback. Done by the hw

string MODE\_AUTO\_HW=automatic\_hw

# Unattended relay detection & activation with inputs/outputs feedback. Done by the sw

string MODE\_AUTO\_SW=automatic\_sw

# Unattended relay detection & and manual activation of the charging relay

string MODE\_MANUAL\_SW=manual\_sw

string operation\_mode

bool contact\_relay\_status # shows if there's contact with the charger

bool charger\_relay\_status # shows if the relay for the charge is active or not

")

(provide :robotnik\_msgs\_new/BatteryDockingStatus "d7c3a4e25e4a4a665c4a1dd0862edfc2")