;; Auto-generated. Do not edit!

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

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

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

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

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

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

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

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

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

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

(in-package "ROS")

(defclass robotnik\_msgs\_new::SetEncoderTurnsRequest

:super ros::object

:slots (\_encoder\_turns ))

(defmethod robotnik\_msgs\_new::SetEncoderTurnsRequest

(:init

(&key

((:encoder\_turns \_\_encoder\_turns) (instance robotnik\_msgs\_new::MotorHeadingOffset :init))

)

(send-super :init)

(setq \_encoder\_turns \_\_encoder\_turns)

self)

(:encoder\_turns

(&rest \_\_encoder\_turns)

(if (keywordp (car \_\_encoder\_turns))

(send\* \_encoder\_turns \_\_encoder\_turns)

(progn

(if \_\_encoder\_turns (setq \_encoder\_turns (car \_\_encoder\_turns)))

\_encoder\_turns)))

(:serialization-length

()

(+

;; robotnik\_msgs\_new/MotorHeadingOffset \_encoder\_turns

(send \_encoder\_turns :serialization-length)

))

(:serialize

(&optional strm)

(let ((s (if strm strm

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

;; robotnik\_msgs\_new/MotorHeadingOffset \_encoder\_turns

(send \_encoder\_turns :serialize s)

;;

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

(:deserialize

(buf &optional (ptr- 0))

;; robotnik\_msgs\_new/MotorHeadingOffset \_encoder\_turns

(send \_encoder\_turns :deserialize buf ptr-) (incf ptr- (send \_encoder\_turns :serialization-length))

;;

self)

)

(defclass robotnik\_msgs\_new::SetEncoderTurnsResponse

:super ros::object

:slots (\_success \_message ))

(defmethod robotnik\_msgs\_new::SetEncoderTurnsResponse

(:init

(&key

((:success \_\_success) nil)

((:message \_\_message) "")

)

(send-super :init)

(setq \_success \_\_success)

(setq \_message (string \_\_message))

self)

(:success

(&optional \_\_success)

(if \_\_success (setq \_success \_\_success)) \_success)

(:message

(&optional \_\_message)

(if \_\_message (setq \_message \_\_message)) \_message)

(:serialization-length

()

(+

;; bool \_success

1

;; string \_message

4 (length \_message)

))

(:serialize

(&optional strm)

(let ((s (if strm strm

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

;; bool \_success

(if \_success (write-byte -1 s) (write-byte 0 s))

;; string \_message

(write-long (length \_message) s) (princ \_message s)

;;

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

(:deserialize

(buf &optional (ptr- 0))

;; bool \_success

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

;; string \_message

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

;;

self)

)

(defclass robotnik\_msgs\_new::SetEncoderTurns

:super ros::object

:slots ())

(setf (get robotnik\_msgs\_new::SetEncoderTurns :md5sum-) "75098e1521736fbeb9e5afbd06f20712")

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

(setf (get robotnik\_msgs\_new::SetEncoderTurns :request) robotnik\_msgs\_new::SetEncoderTurnsRequest)

(setf (get robotnik\_msgs\_new::SetEncoderTurns :response) robotnik\_msgs\_new::SetEncoderTurnsResponse)

(defmethod robotnik\_msgs\_new::SetEncoderTurnsRequest

(:response () (instance robotnik\_msgs\_new::SetEncoderTurnsResponse :init)))

(setf (get robotnik\_msgs\_new::SetEncoderTurnsRequest :md5sum-) "75098e1521736fbeb9e5afbd06f20712")

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

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

"robotnik\_msgs\_new/MotorHeadingOffset encoder\_turns

================================================================================

MSG: robotnik\_msgs\_new/MotorHeadingOffset

int32 motor

float64 value

---

bool success

string message

")

(setf (get robotnik\_msgs\_new::SetEncoderTurnsResponse :md5sum-) "75098e1521736fbeb9e5afbd06f20712")

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

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

"robotnik\_msgs\_new/MotorHeadingOffset encoder\_turns

================================================================================

MSG: robotnik\_msgs\_new/MotorHeadingOffset

int32 motor

float64 value

---

bool success

string message

")

(provide :robotnik\_msgs\_new/SetEncoderTurns "75098e1521736fbeb9e5afbd06f20712")