;; Auto-generated. Do not edit!

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

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

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

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

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

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

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

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

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

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

(in-package "ROS")

(defclass robotnik\_msgs\_new::SetMotorStatusRequest

:super ros::object

:slots (\_status ))

(defmethod robotnik\_msgs\_new::SetMotorStatusRequest

(:init

(&key

((:status \_\_status) 0)

)

(send-super :init)

(setq \_status (round \_\_status))

self)

(:status

(&optional \_\_status)

(if \_\_status (setq \_status \_\_status)) \_status)

(:serialization-length

()

(+

;; int8 \_status

1

))

(:serialize

(&optional strm)

(let ((s (if strm strm

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

;; int8 \_status

(write-byte \_status s)

;;

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

(:deserialize

(buf &optional (ptr- 0))

;; int8 \_status

(setq \_status (sys::peek buf ptr- :char)) (incf ptr- 1)

(if (> \_status 127) (setq \_status (- \_status 256)))

;;

self)

)

(defclass robotnik\_msgs\_new::SetMotorStatusResponse

:super ros::object

:slots (\_ret ))

(defmethod robotnik\_msgs\_new::SetMotorStatusResponse

(:init

(&key

((:ret \_\_ret) nil)

)

(send-super :init)

(setq \_ret \_\_ret)

self)

(:ret

(&optional \_\_ret)

(if \_\_ret (setq \_ret \_\_ret)) \_ret)

(:serialization-length

()

(+

;; bool \_ret

1

))

(:serialize

(&optional strm)

(let ((s (if strm strm

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

;; bool \_ret

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

;;

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

(:deserialize

(buf &optional (ptr- 0))

;; bool \_ret

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

;;

self)

)

(defclass robotnik\_msgs\_new::SetMotorStatus

:super ros::object

:slots ())

(setf (get robotnik\_msgs\_new::SetMotorStatus :md5sum-) "ac25788ee06f4ac013e321c5521c9989")

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

(setf (get robotnik\_msgs\_new::SetMotorStatus :request) robotnik\_msgs\_new::SetMotorStatusRequest)

(setf (get robotnik\_msgs\_new::SetMotorStatus :response) robotnik\_msgs\_new::SetMotorStatusResponse)

(defmethod robotnik\_msgs\_new::SetMotorStatusRequest

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

(setf (get robotnik\_msgs\_new::SetMotorStatusRequest :md5sum-) "ac25788ee06f4ac013e321c5521c9989")

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

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

"# Avalilable status

# 0-> POWER\_ENABLED

# 1-> QUICK\_STOP

# 2-> POWER\_DISABLED (READY\_TO\_SWITCH\_ON)

int8 status

---

bool ret

")

(setf (get robotnik\_msgs\_new::SetMotorStatusResponse :md5sum-) "ac25788ee06f4ac013e321c5521c9989")

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

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

"# Avalilable status

# 0-> POWER\_ENABLED

# 1-> QUICK\_STOP

# 2-> POWER\_DISABLED (READY\_TO\_SWITCH\_ON)

int8 status

---

bool ret

")

(provide :robotnik\_msgs\_new/SetMotorStatus "ac25788ee06f4ac013e321c5521c9989")