;; Auto-generated. Do not edit!

(when (boundp 'robotnik\_msgs\_new::set\_odometry)

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

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

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

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

(make-package "ROBOTNIK\_MSGS\_NEW::SET\_ODOMETRY"))

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

(make-package "ROBOTNIK\_MSGS\_NEW::SET\_ODOMETRYREQUEST"))

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

(make-package "ROBOTNIK\_MSGS\_NEW::SET\_ODOMETRYRESPONSE"))

(in-package "ROS")

(defclass robotnik\_msgs\_new::set\_odometryRequest

:super ros::object

:slots (\_x \_y \_z \_orientation ))

(defmethod robotnik\_msgs\_new::set\_odometryRequest

(:init

(&key

((:x \_\_x) 0.0)

((:y \_\_y) 0.0)

((:z \_\_z) 0.0)

((:orientation \_\_orientation) 0.0)

)

(send-super :init)

(setq \_x (float \_\_x))

(setq \_y (float \_\_y))

(setq \_z (float \_\_z))

(setq \_orientation (float \_\_orientation))

self)

(:x

(&optional \_\_x)

(if \_\_x (setq \_x \_\_x)) \_x)

(:y

(&optional \_\_y)

(if \_\_y (setq \_y \_\_y)) \_y)

(:z

(&optional \_\_z)

(if \_\_z (setq \_z \_\_z)) \_z)

(:orientation

(&optional \_\_orientation)

(if \_\_orientation (setq \_orientation \_\_orientation)) \_orientation)

(:serialization-length

()

(+

;; float32 \_x

4

;; float32 \_y

4

;; float32 \_z

4

;; float32 \_orientation

4

))

(:serialize

(&optional strm)

(let ((s (if strm strm

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

;; float32 \_x

(sys::poke \_x (send s :buffer) (send s :count) :float) (incf (stream-count s) 4)

;; float32 \_y

(sys::poke \_y (send s :buffer) (send s :count) :float) (incf (stream-count s) 4)

;; float32 \_z

(sys::poke \_z (send s :buffer) (send s :count) :float) (incf (stream-count s) 4)

;; float32 \_orientation

(sys::poke \_orientation (send s :buffer) (send s :count) :float) (incf (stream-count s) 4)

;;

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

(:deserialize

(buf &optional (ptr- 0))

;; float32 \_x

(setq \_x (sys::peek buf ptr- :float)) (incf ptr- 4)

;; float32 \_y

(setq \_y (sys::peek buf ptr- :float)) (incf ptr- 4)

;; float32 \_z

(setq \_z (sys::peek buf ptr- :float)) (incf ptr- 4)

;; float32 \_orientation

(setq \_orientation (sys::peek buf ptr- :float)) (incf ptr- 4)

;;

self)

)

(defclass robotnik\_msgs\_new::set\_odometryResponse

:super ros::object

:slots (\_ret ))

(defmethod robotnik\_msgs\_new::set\_odometryResponse

(: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::set\_odometry

:super ros::object

:slots ())

(setf (get robotnik\_msgs\_new::set\_odometry :md5sum-) "34ddd7aa1617c391983fb2ede12712ee")

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

(setf (get robotnik\_msgs\_new::set\_odometry :request) robotnik\_msgs\_new::set\_odometryRequest)

(setf (get robotnik\_msgs\_new::set\_odometry :response) robotnik\_msgs\_new::set\_odometryResponse)

(defmethod robotnik\_msgs\_new::set\_odometryRequest

(:response () (instance robotnik\_msgs\_new::set\_odometryResponse :init)))

(setf (get robotnik\_msgs\_new::set\_odometryRequest :md5sum-) "34ddd7aa1617c391983fb2ede12712ee")

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

(setf (get robotnik\_msgs\_new::set\_odometryRequest :definition-)

"# New robot X position (m)

float32 x

# New robot Y position (m)

float32 y

# New robot Z position (m)

float32 z

# New robot Orientation (rads)

float32 orientation

---

bool ret

")

(setf (get robotnik\_msgs\_new::set\_odometryResponse :md5sum-) "34ddd7aa1617c391983fb2ede12712ee")

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

(setf (get robotnik\_msgs\_new::set\_odometryResponse :definition-)

"# New robot X position (m)

float32 x

# New robot Y position (m)

float32 y

# New robot Z position (m)

float32 z

# New robot Orientation (rads)

float32 orientation

---

bool ret

")

(provide :robotnik\_msgs\_new/set\_odometry "34ddd7aa1617c391983fb2ede12712ee")