

Callback-group-level Executor for ROS 2

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Other node

...

...

Drive-Base node

onEmergencyStopMsg
onCmdVel
publishWheelTicks
reportDiagnosticsData

Other node

...

...

Other node

...
...

Executor

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Other node

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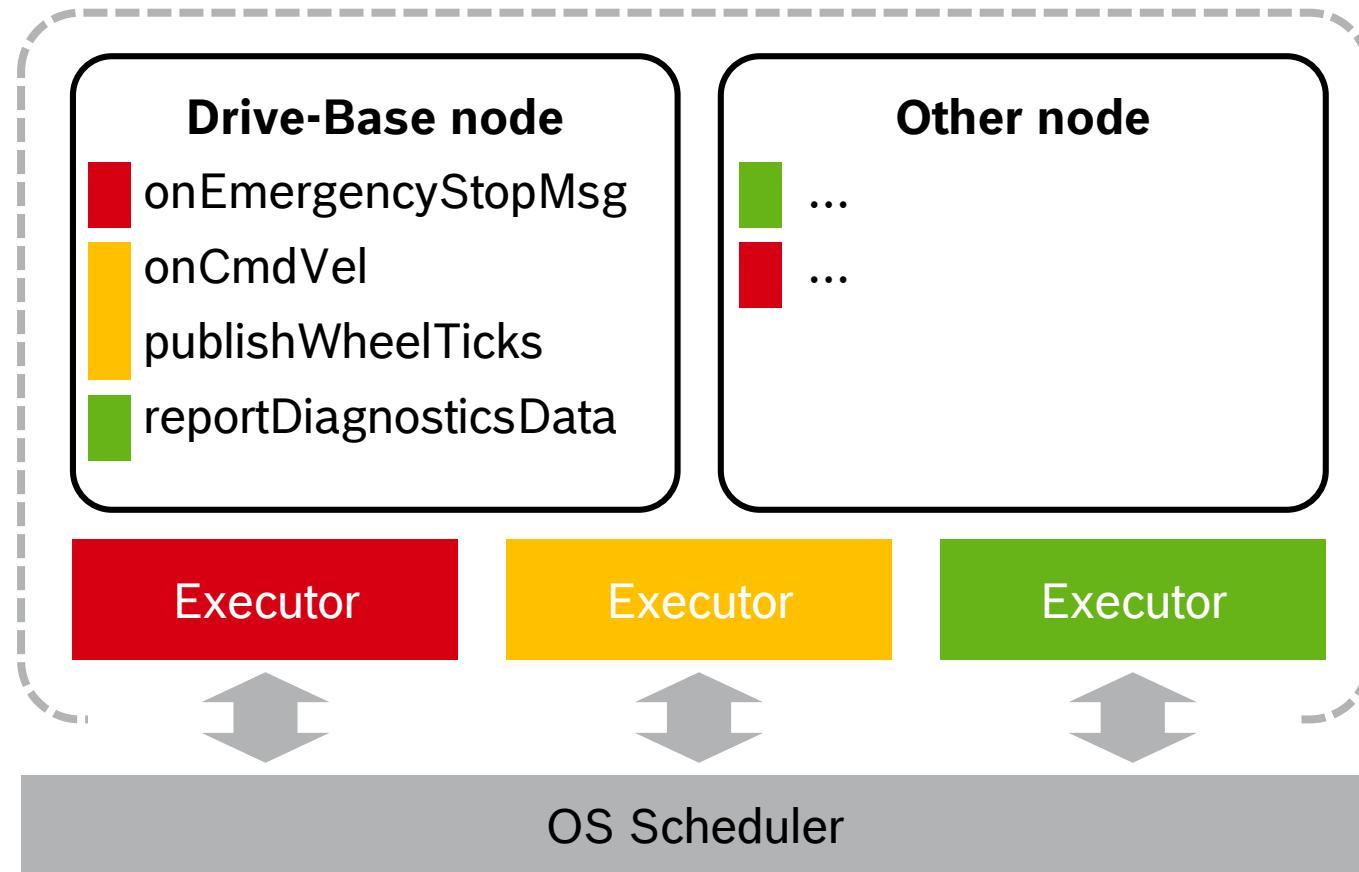
Executor

Drive-Base node

- onEmergencyStopMsg
- onCmdVel
- publishWheelTicks
- reportDiagnosticsData

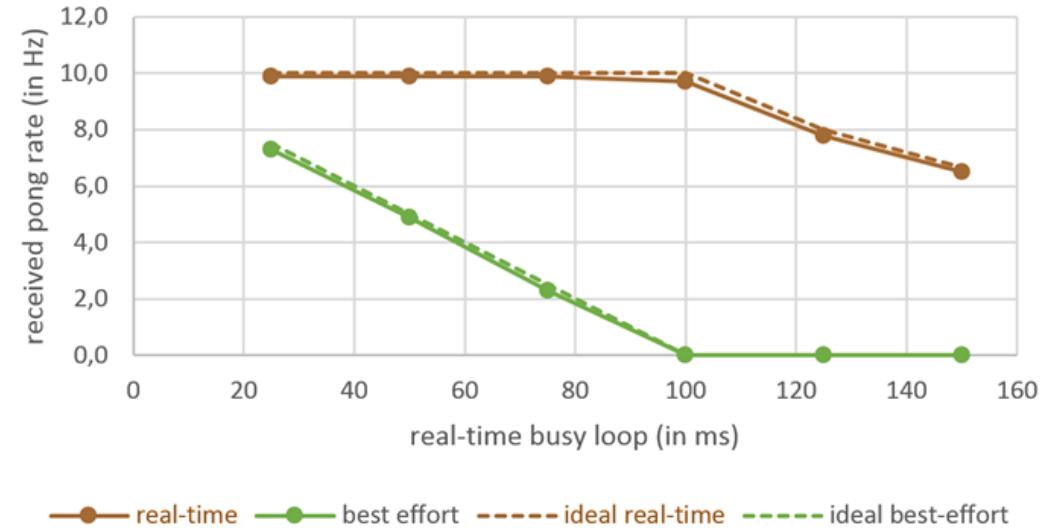
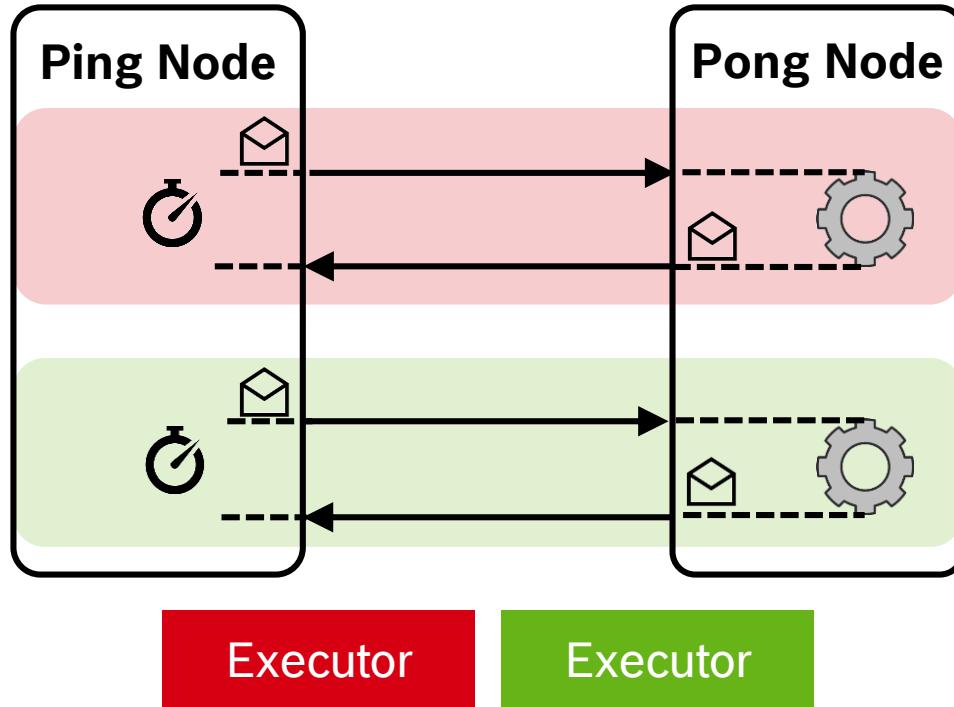
Other node

- ...
- ...



- Refined Executor API: nodes → callback groups
- Refined wait-sets on DDS
- Added scheduling annotations for callback-groups

github.com/boschresearch/ros2_rclcpp → meta-executor



github.com/boschresearch/ros2_examples → meta-executor

Feedback welcome!

Many thanks to William, Karsten and Dakshina!