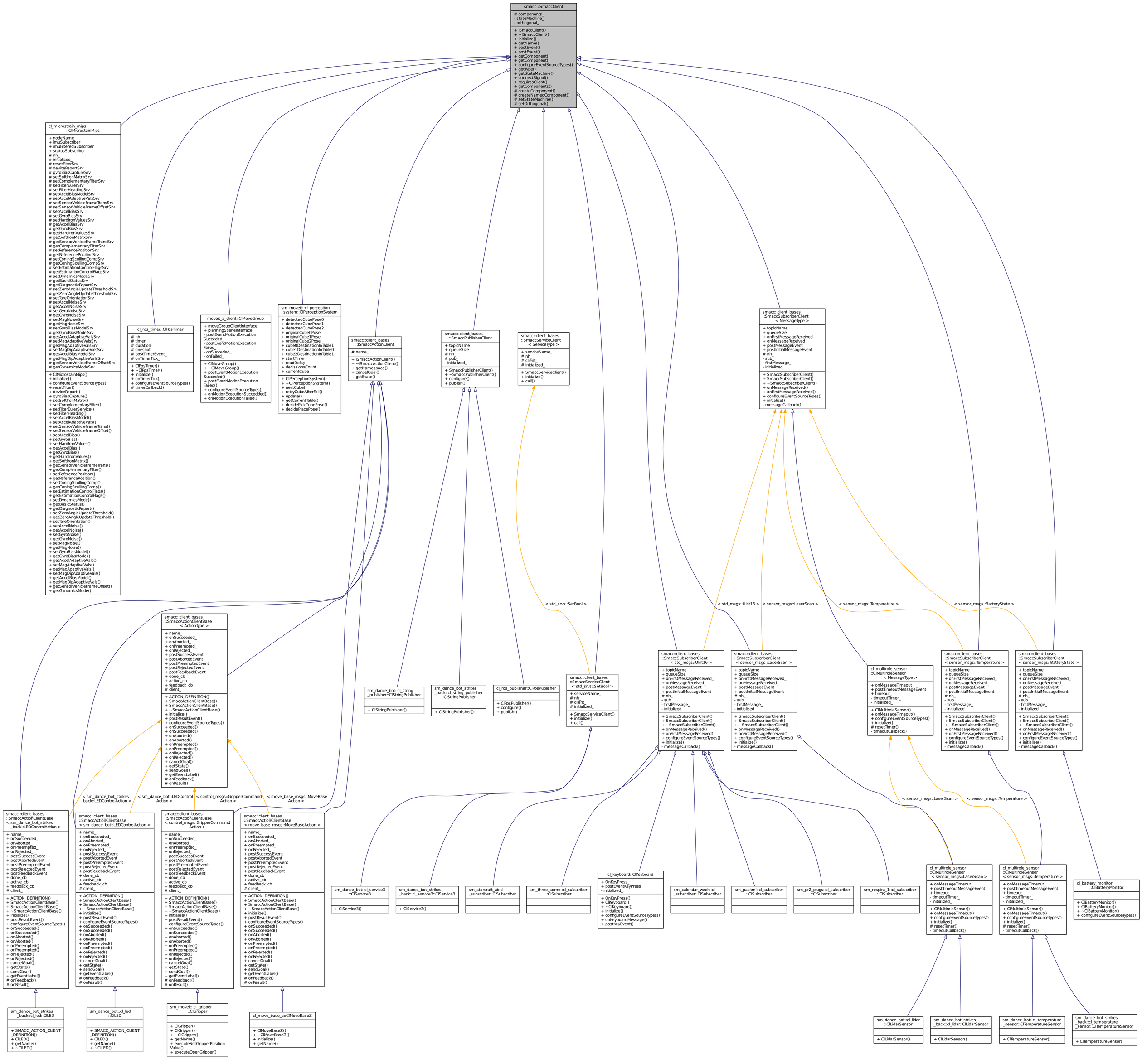
smacc::ISmaccClient
components_
- stateMachine_
- orthogonal_
+ ISmaccClient()
+ ~ISmaccClient()
+ initialize()
+ getName()
+ postEvent()
+ postEvent()
+ getComponent()
+ getComponent()
+ configureEventSourceTypes()
+ getType()
+ getStateMachine()
+ connectSignal()
+ requiresClient()
+ getComponents()
# createComponent()
# createNamedComponent()
# setStateMachine()
# setOrthogonal()
cl_microstrain_mips ::ClMicrostainMips
+ nodeName_
+ imuSubscriber
+ imuFilteredSubscriber
+ statusSubscriber
# nh_
# initialized_
# resetFilterSrv
# deviceReportSrv
# gyroBiasCaptureSrv
# setSoftIronMatrixSrv
# setComplementaryFilterSrv
# setFilterEulerSrv
# setFilterHeadingSrv
# setAccelBiasModelSrv
# setAccelAdaptiveValsSrv
# setSensorVehicleFrameTransSrv
# setSensorVehicleFrameOffsetSrv
# setAccelBiasSrv
# setGyroBiasSrv
# setHardIronValuesSrv
# getAccelBiasSrv
# getGyroBiasSrv
# getHardIronValuesSrv
# getSoftIronMatrixSrv
# getSensorVehicleFrameTransSrv
# getComplementaryFilterSrv
# setReferencePositionSrv
# getReferencePositionSrv
# setConingScullingCompSrv
# getConingScullingCompSrv
# setEstimationControlFlagsSrv
# getEstimationControlFlagsSrv
# setDynamicsModeSrv
# getBasicStatusSrv
# getDiagnosticReportSrv
# setZeroAngleUpdateThresholdSrv
# getZeroAngleUpdateThresholdSrv
# setTareOrientationSrv
# setAccelNoiseSrv
# getAccelNoiseSrv
# setGyroNoiseSrv
# getGyroNoiseSrv
# setMagNoiseSrv
# getMagNoiseSrv
# setGyroBiasModelSrv
# getGyroBiasModelSrv
# getAccelAdaptiveValsSrv
# setMagAdaptiveValsSrv
# getMagAdaptiveValsSrv
# setMagDipAdaptiveValsSrv
# getSensorVehicleFrameOffsetSrv
# getGynamicsModeSrv
+ ClMicrostainMips()
+ initialize()
+ configureEventSourceTypes()
+ resetFilter()
+ deviceReport()
+ gyroBiasCapture()
+ setSoftIronMatrix()
+ setComplementaryFilter()
+ setFilterEulerService()
+ setFilterHeading()
+ setAccelBiasModel()
+ setAccelAdaptiveVals()
+ setSensorVehicleFrameTrans()
+ setSensorVehicleFrameOffset()
+ setAccelBias()
+ setGyroBias()
+ setHardIronValues()
+ getAccelBias()
+ getGyroBias()
+ getHardIronValues()
+ getSoftIronMatrix()
+ getSensorVehicleFrameTrans()
+ getComplementaryFilter()
+ setReferencePosition()
+ getReferencePosition()
+ setConingScullingComp()
+ getConingScullingComp()
+ setEstimationControlFlags()
+ getEstimationControlFlags()
+ setDynamicsMode()
+ getBasicStatus()
+ getDiagnosticReport()
+ setZeroAngleUpdateThreshold()
+ getZeroAngleUpdateThreshold()
+ setTareOrientation()
+ setAccelNoise()
+ getAccelNoise()
+ setGyroNoise()
+ getGyroNoise()
+ setMagNoise()
+ getMagNoise()
+ setGyroBiasModel()
+ getGyroBiasModel()
+ getAccelAdaptiveVals()
+ setMagAdaptiveVals()
+ getMagAdaptiveVals()
+ setMagDipAdaptiveVals()
+ getAccelBiasModel()
+ getMagDipAdaptiveVals()
+ getSensorVehicleFrameOffset()
+ getGynamicsMode()
cl_ros_timer::ClRosTimer
nh_
timer
duration
oneshot
postTimerEvent_
onTimerTick_
+ ClRosTimer()
+ ~ClRosTimer()
+ initialize()
+ onTimerTick()
+ configureEventSourceTypes()
# timerCallback()
moveit_z_client::ClMoveGroup
+ moveGroupClientInterface
+ planningSceneInterface
- postEventMotionExecution Succeded_
- postEveritMotionExecution Failed_
- onSucceded_
- onFailed_
+ ClMoveGroup()
+ ~ClMoveGroup()
+ postEventMotionExecution Succeded()
+ postEventMotionExecution Failed()
+ configureEventSourceTypes()
+ onMotionExecutionSuccedded()
+ onMotionExecutionFailed()
sm_moveit::cl_perception _system::ClPerceptionSystem
+ detectedCubePose0
+ detectedCubePose1
+ detectedCubePose2
+ originalCube0Pose
+ originalCube1Pose
+ originalCube2Pose
+ cube0DestinationInTable1
+ cube1DestinationInTable0
+ cube2DestinationInTable1
+ startTime
+ readDelay
+ decissionsCount
+ currentCube
+ ClPerceptionSystem()
+ ~ClPerceptionSystem()
+ nextCube()
+ retryCubeAfterFail()
+ update()
+ getCurrentTable()
+ decidePickCubePose()
+ decidePlacePose()
smacc::client_bases ::ISmaccActionClient
name_
+ ISmaccActionClient()
+ ~ISmaccActionClient()
+ getNamespace()
+ cancelGoal()
+ getState()
smacc::client_bases ::SmaccPublisherClient
+ topicName
+ queueSize
# nh_
# pub_
- initialized_
+ SmaccPublisherClient()
+ ~SmaccPublisherClient()
+ configure()
+ publish()
smacc::client_bases ::SmaccServiceClient < ServiceType >
+ serviceName_
# nh_
# client_
# initialized_
+ SmaccServiceClient()
+ initialize()
+ call()
smacc::client_bases ::SmaccSubscriberClient < MessageType >
+ topicName
+ queueSize
+ onFirstMessageReceived_
+ onMessageReceived_
+ postMessageEvent
+ postInitialMessageEvent
# nh_
- sub_
- firstMessage_
- initialized_
+ SmaccSubscriberClient()
+ SmaccSubscriberClient()
+ ~SmaccSubscriberClient()
+ onMessageReceived()
+ onFirstMessageReceived()
+ configureEventSourceTypes()
+ initialize()
- messageCallback()
< std_srvs::SetBool >
< std_msgs::UInt16 >
< sensor_msgs::LaserScan >
< sensor_msgs::Temperature >
< sensor_msgs::BatteryState >
smacc::client_bases ::SmaccActionClientBase < ActionType >
+ name_
+ onSucceeded_
+ onAborted_
+ onPreempted_
+ onRejected_
+ postSuccessEvent
+ postAbortedEvent
+ postPreemptedEvent
+ postRejectedEvent
+ postFeedbackEvent
+ done_cb
+ active_cb
+ feedback_cb
# client_
+ ACTION_DEFINITION()
+ SmaccActionClientBase()
+ SmaccActionClientBase()
+ ~SmaccActionClientBase()
+ initialize()
+ postResultEvent()
+ configureEventSourceTypes()
+ onSucceeded()
+ onSucceeded()
+ onAborted()
+ onAborted()
+ onPreempted()
+ onPreempted()
+ onRejected()
+ onRejected()
+ cancelGoal()
+ getState()
+ sendGoal()
+ getEventLabel()
# onFeedback()
# onResult()
sm_dance_bot::cl_string _publisher::ClStringPublisher
+ ClStringPublisher()
sm_dance_bot_strikes _back::cl_string_publisher ::ClStringPublisher
+ ClStringPublisher()
cl_ros_publisher::ClRosPublisher
+ ClRosPublisher()
+ configure()
+ publish()
smacc::client_bases ::SmaccServiceClient < std_srvs::SetBool >
+ serviceName_
# nh_
# client_
# initialized_
+ SmaccServiceClient()
+ initialize()
+ call()
smacc::client_bases ::SmaccSubscriberClient < std_msgs::UInt16 >
+ topicName
+ queueSize
+ onFirstMessageReceived_
+ onMessageReceived_
+ postMessageEvent
+ postInitialMessageEvent
# nh_
- sub_
- firstMessage_
- initialized_
+ SmaccSubscriberClient()
+ SmaccSubscriberClient()
+ ~SmaccSubscriberClient()
+ onMessageReceived()
+ onFirstMessageReceived()
+ configureEventSourceTypes()
+ initialize()
- messageCallback()
smacc::client_bases ::SmaccSubscriberClient < sensor_msgs::LaserScan >
+ topicName
+ queueSize
+ onFirstMessageReceived_
+ onMessageReceived_
+ postMessageEvent
+ postInitialMessageEvent
# nh_
- sub_
- firstMessage_
- initialized_
+ SmaccSubscriberClient()
+ SmaccSubscriberClient()
+ ~SmaccSubscriberClient()
+ onMessageReceived()
+ onFirstMessageReceived()
+ configureEventSourceTypes()
+ initialize()
- messageCallback()
cl_multirole_sensor ::ClMultiroleSensor < MessageType >
+ onMessageTimeout_
+ postTimeoutMessageEvent
+ timeout_
- timeoutTimer_
- initialized_
+ ClMultiroleSensor()
+ onMessageTimeout()
+ configureEventSourceTypes()
+ initialize()
# resetTimer()
- timeoutCallback()
smacc::client_bases ::SmaccSubscriberClient < sensor_msgs::Temperature >
+ topicName
+ queueSize
+ onFirstMessageReceived_
+ onMessageReceived_
+ postMessageEvent
+ postInitialMessageEvent
# nh_
- sub_
- firstMessage_
- initialized_
+ SmaccSubscriberClient()
+ SmaccSubscriberClient()
+ ~SmaccSubscriberClient()
+ onMessageReceived()
+ onFirstMessageReceived()
+ configureEventSourceTypes()
+ initialize()
- messageCallback()
smacc::client_bases ::SmaccSubscriberClient < sensor_msgs::BatteryState >
+ topicName
+ queueSize
+ onFirstMessageReceived_
+ onMessageReceived_
+ postMessageEvent
+ postInitialMessageEvent
# nh_
- sub_
- firstMessage_
- initialized_
+ SmaccSubscriberClient()
+ SmaccSubscriberClient()
+ ~SmaccSubscriberClient()
+ onMessageReceived()
+ onFirstMessageReceived()
+ configureEventSourceTypes()
+ initialize()
- messageCallback()
< sm_dance_bot_strikes _back::LEDControlAction >
< sm_dance_bot::LEDControl Action >
< control_msgs::GripperCommand Action >
< move_base_msgs::MoveBase Action >
< sensor_msgs::LaserScan >
< sensor_msgs::Temperature >
smacc::client_bases ::SmaccActionClientBase < sm_dance_bot_strikes _back::LEDControlAction >
+ name_
+ onSucceeded_
+ onAborted_
+ onPreempted_
+ onRejected_
+ postSuccessEvent
+ postAbortedEvent
+ postPreemptedEvent
+ postRejectedEvent
+ postFeedbackEvent
+ done_cb
+ active_cb
+ feedback_cb
# client_
+ ACTION_DEFINITION()
+ SmaccActionClientBase()
+ SmaccActionClientBase()
+ ~SmaccActionClientBase()
+ initialize()
+ postResultEvent()
+ configureEventSourceTypes()
+ onSucceeded()
+ onSucceeded()
+ onAborted()
+ onAborted()
+ onPreempted()
+ onPreempted()
+ onRejected()
+ onRejected()
+ cancelGoal()
+ getState()
+ sendGoal()
+ getEventLabel()
# onFeedback()
# onResult()
smacc::client_bases ::SmaccActionClientBase < sm_dance_bot::LEDControlAction >
+ name_
+ onSucceeded_
+ onAborted_
+ onPreempted_
+ onRejected_
+ postSuccessEvent
+ postAbortedEvent
+ postPreemptedEvent
+ postRejectedEvent
+ postFeedbackEvent
+ done_cb
+ active_cb
+ feedback_cb
# client_
+ ACTION_DEFINITION()
+ SmaccActionClientBase()
+ SmaccActionClientBase()
+ ~SmaccActionClientBase()
+ initialize()
+ postResultEvent()
+ configureEventSourceTypes()
+ onSucceeded()
+ onSucceeded()
+ onAborted()
+ onAborted()
+ onPreempted()
+ onPreempted()
+ onRejected()
+ onRejected()
+ cancelGoal()
+ getState()
+ sendGoal()
+ getEventLabel()
# onFeedback()
# onResult()
smacc::client_bases ::SmaccActionClientBase < control_msgs::GripperCommand Action >
+ name_
+ onSucceeded_
+ onAborted_
+ onPreempted_
+ onRejected_
+ postSuccessEvent
+ postAbortedEvent
+ postPreemptedEvent
+ postRejectedEvent
+ postFeedbackEvent
+ done_cb
+ active_cb
+ feedback_cb
# client_
+ ACTION_DEFINITION()
+ SmaccActionClientBase()
+ SmaccActionClientBase()
+ ~SmaccActionClientBase()
+ initialize()
+ postResultEvent()
+ configureEventSourceTypes()
+ onSucceeded()
+ onSucceeded()
+ onAborted()
+ onAborted()
+ onPreempted()
+ onPreempted()
+ onRejected()
+ onRejected()
+ cancelGoal()
+ getState()
+ sendGoal()
+ getEventLabel()
# onFeedback()
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smacc::client_bases ::SmaccActionClientBase < move_base_msgs::MoveBaseAction >
+ name_
+ onSucceeded_
+ onAborted_
+ onPreempted_
+ onRejected_
+ postSuccessEvent
+ postAbortedEvent
+ postPreemptedEvent
+ postRejectedEvent
+ postFeedbackEvent
+ done_cb
+ active_cb
+ feedback_cb
# client_
+ ACTION_DEFINITION()
+ SmaccActionClientBase()
+ SmaccActionClientBase()
+ ~SmaccActionClientBase()
+ initialize()
+ postResultEvent()
+ configureEventSourceTypes()
+ onSucceeded()
+ onSucceeded()
+ onAborted()
+ onAborted()
+ onPreempted()
+ onPreempted()
+ onRejected()
+ onRejected()
+ cancelGoal()
+ getState()
+ sendGoal()
+ getEventLabel()
# onFeedback()
# onResult()
sm_dance_bot::cl_service3 ::ClService3
+ ClService3()
sm_dance_bot_strikes _back::cl_service3::ClService3
+ ClService3()
sm_starcraft_ai::cl _subscriber::ClSubscriber
sm_three_some::cl_subscriber ::ClSubscriber
cl_keyboard::ClKeyboard
+ OnKeyPress_
+ postEventKeyPress
- initialized_
+ OnKeyPress()
+ ClKeyboard()
+ ~ClKeyboard()
+ initialize()
+ configureEventSourceTypes()
+ onKeyboardMessage()
+ postKeyEvent()
sm_calendar_week::cl _subscriber::ClSubscriber
sm_packml::cl_subscriber ::ClSubscriber
sm_pr2_plugs::cl_subscriber ::ClSubscriber
sm_respira_1::cl_subscriber ::ClSubscriber
cl_multirole_sensor ::ClMultiroleSensor < sensor_msgs::LaserScan >
+ onMessageTimeout_
+ postTimeoutMessageEvent
+ timeout_
- timeoutTimer_
- initialized_
+ ClMultiroleSensor()
+ onMessageTimeout()
+ configureEventSourceTypes()
+ initialize()
# resetTimer()
- timeoutCallback()
cl_multirole_sensor ::ClMultiroleSensor < sensor_msgs::Temperature >
+ onMessageTimeout_
+ postTimeoutMessageEvent
+ timeout_
- timeoutTimer_
- initialized_
+ ClMultiroleSensor()
+ onMessageTimeout()
+ configureEventSourceTypes()
+ initialize()
# resetTimer()
- timeoutCallback()
cl_battery_monitor ::ClBatteryMonitor
+ ClBatteryMonitor()
+ ClBatteryMonitor()
+ ~ClBatteryMonitor()
+ configureEventSourceTypes()
sm_dance_bot_strikes _back::cl_led::ClLED
+ SMACC_ACTION_CLIENT _DEFINITION()
+ ClLED()
+ getName()
+ ~ClLED()
sm_dance_bot::cl_led ::ClLED
+ SMACC_ACTION_CLIENT _DEFINITION()
+ ClLED()
+ getName()
+ ~ClLED()
sm_moveit::cl_gripper ::ClGripper
+ ClGripper()
+ ClGripper()
+ ~ClGripper()
+ getName()
+ executeSetGripperPosition Value()
+ executeOpenGripper()
cl_move_base_z::ClMoveBaseZ
+ ClMoveBaseZ()
+ ~ClMoveBaseZ()
+ initialize()
+ getName()
sm_dance_bot::cl_lidar ::ClLidarSensor
+ ClLidarSensor()
sm_dance_bot_strikes _back::cl_lidar::ClLidarSensor
+ ClLidarSensor()
sm_dance_bot::cl_temperature _sensor::ClTemperatureSensor
+ ClTemperatureSensor()
sm_dance_bot_strikes _back::cl_temperature _sensor::ClTemperatureSensor
+ ClTemperatureSensor()