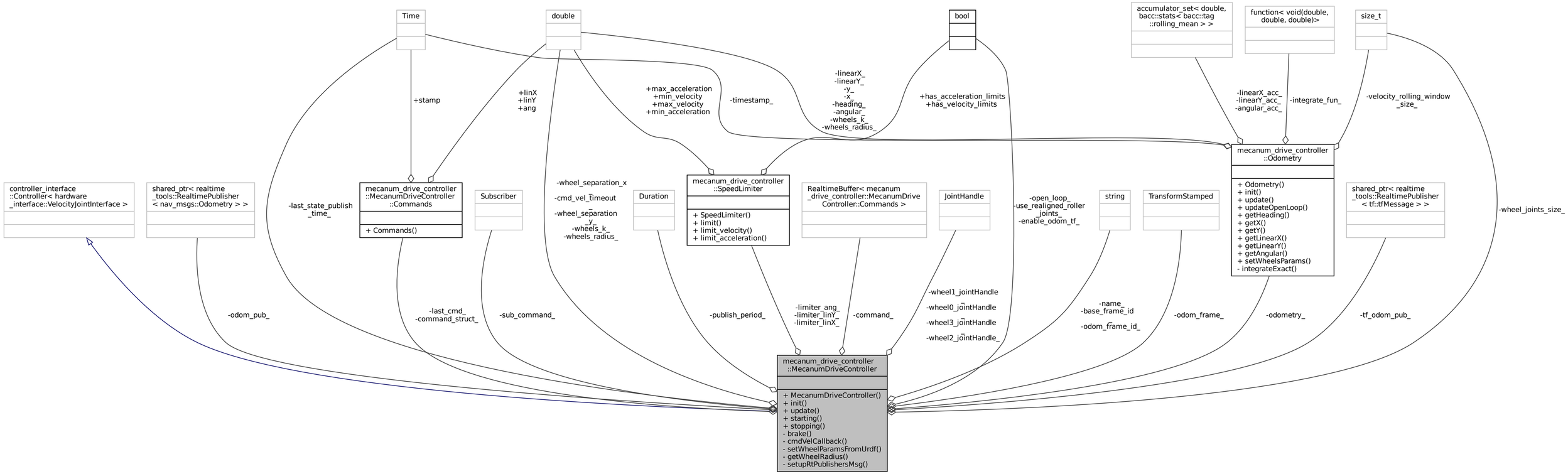
Time
double
bool
accumulator_set< double, bacc::stats< bacc::tag ::rolling_mean > >
function< void(double, double, double)>
size_t
controller_interface ::Controller< hardware _interface::VelocityJointInterface >
shared_ptr< realtime _tools::RealtimePublisher < nav_msgs::Odometry > >
mecanum_drive_controller ::MecanumDriveController ::Commands
+ Commands()
Subscriber
Duration
mecanum_drive_controller ::SpeedLimiter
+ SpeedLimiter()
+ limit()
+ limit_velocity()
+ limit_acceleration()
RealtimeBuffer< mecanum _drive_controller::MecanumDrive Controller::Commands >
JointHandle
string
TransformStamped
mecanum_drive_controller ::Odometry
+ Odometry()
+ init()
+ update()
+ updateOpenLoop()
+ getHeading()
+ getX()
+ getY()
+ getLinearX()
+ getLinearY()
+ getAngular()
+ setWheelsParams()
- integrateExact()
shared_ptr< realtime _tools::RealtimePublisher < tf::tfMessage > >
mecanum_drive_controller ::MecanumDriveController
+ MecanumDriveController()
+ init()
+ update()
+ starting()
+ stopping()
- brake()
- cmdVelCallback()
- setWheelParamsFromUrdf()
- getWheelRadius()
- setupRtPublishersMsg()
+stamp
+linX
+linY
+ang
+max_acceleration
+min_velocity
+max_velocity
+min_acceleration
-timestamp_
-linearX_
-linearY_
-y_
-x_
-heading_
-angular_
-wheels_k_
-wheels_radius_
+has_acceleration_limits
+has_velocity_limits
-linearX_acc_
-linearY_acc_
-angular_acc_
-integrate_fun_
-velocity_rolling_window _size_
-wheel_joints_size_
-last_state_publish _time_
-wheel_separation_x
-cmd_vel_timeout
-wheel_separation _y_
-wheels_k_
-wheels_radius_
-open_loop_
-use_realigned_roller _joints_
-enable_odom_tf_
-odom_pub_
-last_cmd_ -command_struct_
-sub_command_
-publish_period_
-limiter_ang_
-limiter_linY_
-limiter_linX_
-command_
-wheel1_jointHandle
-wheel0_jointHandle
-wheel3_jointHandle
-wheel2_jointHandle_
-name_
-base_frame_id
-odom_frame_id_
-odom_frame_
-odometry_
-tf_odom_pub_