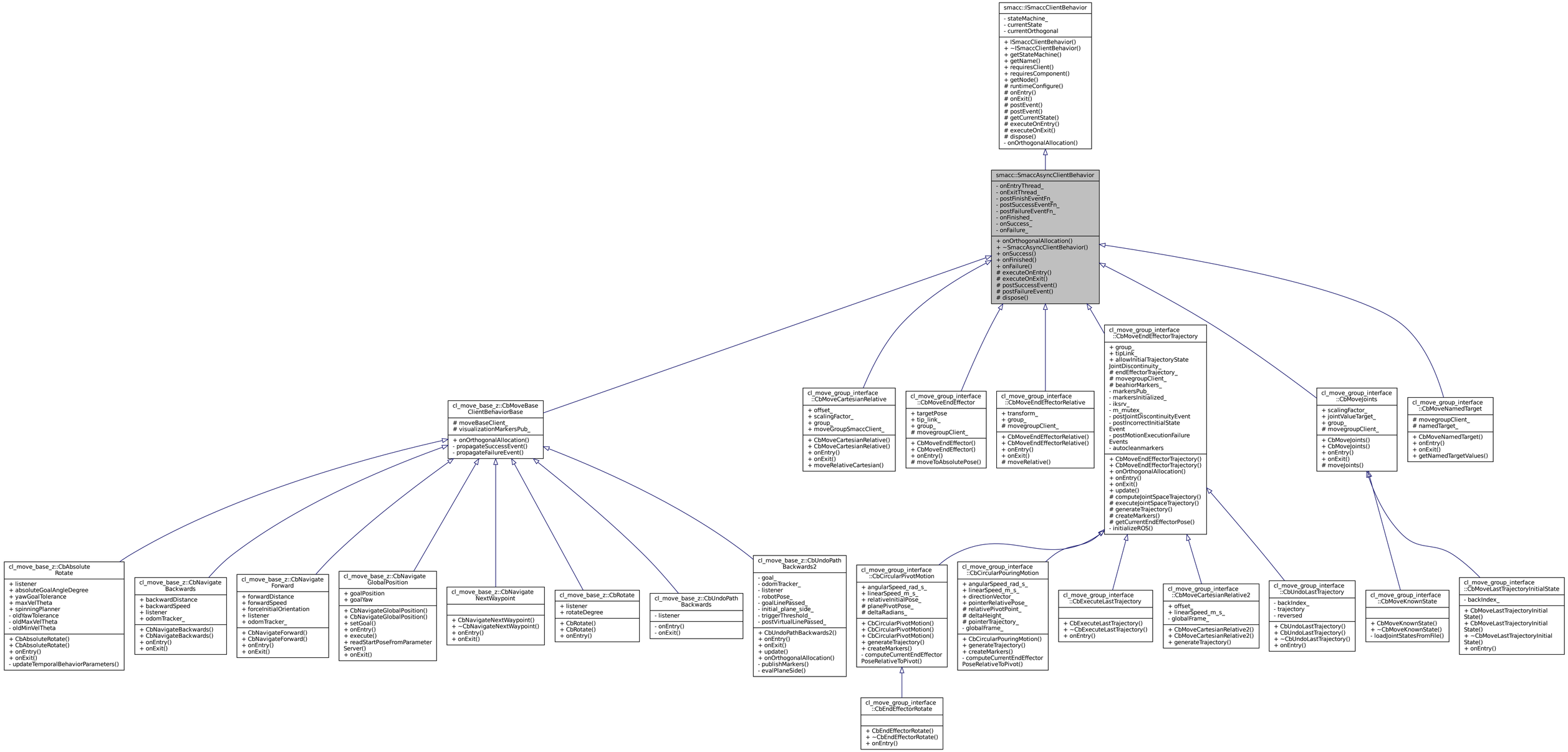
smacc::ISmaccClientBehavior
- stateMachine_
- currentState
- currentOrthogonal
+ ISmaccClientBehavior()
+ ~ISmaccClientBehavior()
+ getStateMachine()
+ getName()
+ requiresClient()
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+ getNode()
# runtimeConfigure()
# onEntry()
# onExit()
# postEvent()
# postEvent()
# getCurrentState()
# executeOnEntry()
# executeOnExit()
# dispose()
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- onExitThread_
- postFinishEventFn_
- postSuccessEventFn_
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- onFinished_
- onSuccess_
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+ ~SmaccAsyncClientBehavior()
+ onSuccess()
+ onFinished()
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# executeOnEntry()
# executeOnExit()
# postSuccessEvent()
# postFailureEvent()
# dispose()
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+ onOrthogonalAllocation()
- propagateSuccessEvent()
- propagateFailureEvent()
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+ offset_
+ scalingFactor_
+ group_
+ moveGroupSmaccClient_
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+ CbMoveCartesianRelative()
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+ moveRelativeCartesian()
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+ targetPose
+ tip_link_
+ group_
# movegroupClient_
+ CbMoveEndEffector()
+ CbMoveEndEffector()
+ onEntry()
# moveToAbsolutePose()
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+ transform_
+ group_
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+ CbMoveEndEffectorRelative()
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+ tipLink_
+ allowInitialTrajectoryState
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endEffectorTrajectory_
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- markersPub_
- markersInitialized_
- iksrv_
- m_mutex_
- postJointDiscontinuityEvent
- postIncorrectInitialState
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- postMotionExecutionFailure
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- autocleanmarkers
+ CbMoveEndEffectorTrajectory()
+ CbMoveEndEffectorTrajectory()
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- initializeROS()
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+ scalingFactor_
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+ CbMoveJoints()
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+ listener
+ absoluteGoalAngleDegree
+ yawGoalTolerance
+ maxVelTheta
+ spinningPlanner
- oldYawTolerance
- oldMaxVelTheta
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+ CbAbsoluteRotate()
+ CbAbsoluteRotate()
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- updateTemporalBehaviorParameters()
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+ CbNavigateForward()
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+ goalPosition
+ goalYaw
+ CbNavigateGlobalPosition()
+ CbNavigateGlobalPosition()
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+ CbNavigateNextWaypoint()
+ ~CbNavigateNextWaypoint()
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+ listener
+ rotateDegree
+ CbRotate()
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cl_move_base_z::CbUndoPath
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+ CbExecuteLastTrajectory()
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+ CbMoveKnownState()
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+ CbMoveLastTrajectoryInitial
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+ CbMoveLastTrajectoryInitial
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