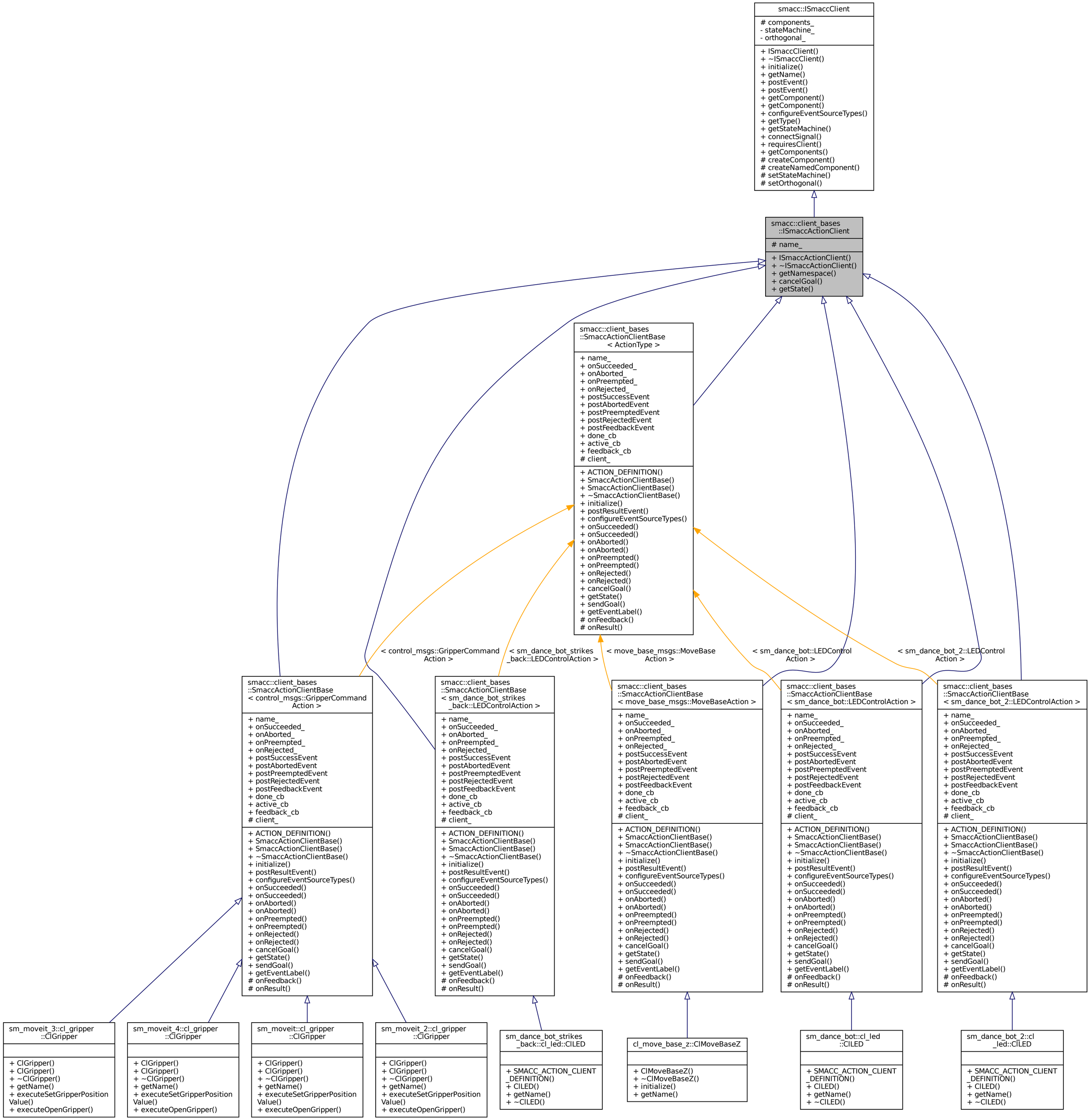
smacc::ISmaccClient
components_
- stateMachine_
- orthogonal_
+ ISmaccClient()
+ ~ISmaccClient()
+ initialize()
+ getName()
+ postEvent()
+ postEvent()
+ getComponent()
+ getComponent()
+ configureEventSourceTypes()
+ getType()
+ getStateMachine()
+ connectSignal()
+ requiresClient()
+ getComponents()
# createComponent()
# createNamedComponent()
# setStateMachine()
# setOrthogonal()
smacc::client_bases
::ISmaccActionClient
name_
+ ISmaccActionClient()
+ ~ISmaccActionClient()
+ getNamespace()
+ cancelGoal()
+ getState()
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()
< control_msgs::GripperCommand
Action >
< sm_dance_bot_strikes
_back::LEDControlAction >
< move_base_msgs::MoveBase
Action >
< sm_dance_bot::LEDControl
Action >
< sm_dance_bot_2::LEDControl
Action >
smacc::client_bases
::SmaccActionClientBase
< control_msgs::GripperCommand
Action >
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+ onSucceeded_
+ onAborted_
+ onPreempted_
+ onRejected_
+ postSuccessEvent
+ postAbortedEvent
+ postPreemptedEvent
+ postRejectedEvent
+ postFeedbackEvent
+ done_cb
+ active_cb
+ feedback_cb
# client_
+ ACTION_DEFINITION()
+ SmaccActionClientBase()
+ SmaccActionClientBase()
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+ initialize()
+ postResultEvent()
+ configureEventSourceTypes()
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+ onRejected()
+ cancelGoal()
+ getState()
+ sendGoal()
+ getEventLabel()
# onFeedback()
# onResult()
smacc::client_bases
::SmaccActionClientBase
< sm_dance_bot_strikes
_back::LEDControlAction >
+ name_
+ onSucceeded_
+ onAborted_
+ onPreempted_
+ onRejected_
+ postSuccessEvent
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+ onRejected()
+ onRejected()
+ cancelGoal()
+ getState()
+ sendGoal()
+ getEventLabel()
# onFeedback()
# onResult()
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()
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+ onAborted()
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+ 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()
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+ onRejected()
+ onRejected()
+ cancelGoal()
+ getState()
+ sendGoal()
+ getEventLabel()
# onFeedback()
# onResult()
smacc::client_bases
::SmaccActionClientBase
< sm_dance_bot_2::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()
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+ onAborted()
+ onPreempted()
+ onPreempted()
+ onRejected()
+ onRejected()
+ cancelGoal()
+ getState()
+ sendGoal()
+ getEventLabel()
# onFeedback()
# onResult()
sm_moveit_3::cl_gripper
::ClGripper
+ ClGripper()
+ ClGripper()
+ ~ClGripper()
+ getName()
+ executeSetGripperPosition
Value()
+ executeOpenGripper()
sm_moveit_4::cl_gripper
::ClGripper
+ ClGripper()
+ ClGripper()
+ ~ClGripper()
+ getName()
+ executeSetGripperPosition
Value()
+ executeOpenGripper()
sm_moveit::cl_gripper
::ClGripper
+ ClGripper()
+ ClGripper()
+ ~ClGripper()
+ getName()
+ executeSetGripperPosition
Value()
+ executeOpenGripper()
sm_moveit_2::cl_gripper
::ClGripper
+ ClGripper()
+ ClGripper()
+ ~ClGripper()
+ getName()
+ executeSetGripperPosition
Value()
+ executeOpenGripper()
sm_dance_bot_strikes
_back::cl_led::ClLED
+ SMACC_ACTION_CLIENT
_DEFINITION()
+ ClLED()
+ getName()
+ ~ClLED()
cl_move_base_z::ClMoveBaseZ
+ ClMoveBaseZ()
+ ~ClMoveBaseZ()
+ initialize()
+ getName()
sm_dance_bot::cl_led
::ClLED
+ SMACC_ACTION_CLIENT
_DEFINITION()
+ ClLED()
+ getName()
+ ~ClLED()
sm_dance_bot_2::cl
_led::ClLED
+ SMACC_ACTION_CLIENT
_DEFINITION()
+ ClLED()
+ getName()
+ ~ClLED()