cl_move_base_z::CbUndoPath
Backwards2
+ CbUndoPathBackwards2()
+ onEntry()
+ onExit()
+ update()
+ onOrthogonalAllocation()
- publishMarkers()
- evalPlaneSide()
Goal
float
TransformListener
-goal_
-triggerThreshold_
-initial_plane_side_
-listener_
-odomTracker_
-robotPose_
-goalLinePassed_
-postVirtualLinePassed_
cl_move_base_z::CbMoveBase
ClientBehaviorBase
+ onOrthogonalAllocation()
- propagateSuccessEvent()
- propagateFailureEvent()
#moveBaseClient_
cl_move_base_z::ClMoveBaseZ
+ ClMoveBaseZ()
+ ~ClMoveBaseZ()
+ initialize()
+ getName()
smacc::client_bases
::SmaccActionClientBase
< move_base_msgs::MoveBaseAction >
< move_base_msgs::MoveBase
Action >
smacc::client_bases
::SmaccActionClientBase
< ActionType >
smacc::client_bases
::ISmaccActionClient
smacc::SmaccAsyncClientBehavior
smacc::ISmaccClientBehavior
smacc::ISmaccClient
smacc::ISmaccOrthogonal
smacc::ISmaccStateMachine
smacc::ISmaccState
smacc::introspection
::SmaccStateInfo
smacc::SignalDetector
smacc::ISmaccComponent
smacc::ISmaccUpdatable
cl_move_base_z::odom
_tracker::OdomTracker
cl_move_base_z::Pose
smacc::SmaccSignal
< void()>
smacc::SmaccSignal
< void(const ResultConstPtr &)>
type_info *
std::enable_shared
_from_this< SmaccStateInfo >
string
NodeHandle
Publisher
ServiceServer
unsigned long
StateMachineInternalAction
Timer
SmaccStatus
recursive_mutex
SMRunMode
processor_handle
SmaccFifoScheduler *
thread
atomic< unsigned long >
atomic< bool >
double
bool
mutex
PoseStamped
Time
optional< ros::Duration >
CallbackType
Path
Subscriber
WorkingMode
SimpleDoneCallback
SimpleFeedbackCallback
SimpleActiveCallback
function< void()>
future< int >
shared_ptr< ActionClient >
vector< nav_msgs::Path >
#stateInfo_
#currentStateInfo_
#currentState_
#parentState_
#stateMachine_
-stateMachine_
-currentState
-currentOrthogonal
-orthogonal_
#clients_
-clientBehaviors_
#components_
#owner_
-stateMachineInfo_
#transitionHistoryService_
-stateSeqCounter_
-stateMachineCurrentAction
#timer_
#status_msg_
-eventQueueMutex_
-m_mutex_
#private_nh_
#nh_
-globalData_
#orthogonals_
-stateCallbackConnections
-runMode_
-transitionLogHistory_
#transitionLogPub_
#stateMachineStatusPub
#stateMachinePub_
-nh_
-statusPub_
-smaccStateMachine_
-signalDetector_
-processorHandle_
-scheduler_
-updatableClients_
-updatableStateElements_
-signalDetectorThread_
-lastState_
-initialized_
-end_
-loop_rate_hz
+name_
#name_
#odomFrame_
-referenceFrame_
-poseFrameName_
#client_
+done_cb
+feedback_cb
+active_cb
+postFeedbackEvent
+postRejectedEvent
+postAbortedEvent
+postPreemptedEvent
+postSuccessEvent
+onSucceeded_
+onAborted_
+onPreempted_
+onRejected_
-onEntryThread_
-onExitThread_
-onFinished_
-onSuccess_
-onFailure_
-postFinishEventFn
-postSuccessEventFn
-postFailureEventFn_
< void()>
< void(const ResultConst
Ptr &)>
#pathStack_
#clearPointDistanceThreshold
#recordPointDistanceThreshold
#clearAngularDistanceThreshold
#recordAngularDistanceThreshold_
#baseTrajectory_
#aggregatedStackPathMsg
#robotBasePathStackedPub
#robotBasePathPub_
#odomSub_
#workingMode_
#publishMessages
#subscribeToOdometryTopic_
+isInitialized
#m_mutex_
-listenerMutex_
-m_mutex_
-pose_
-tfListener_
-lastUpdate_
-periodDuration_
#visualizationMarkersPub_
#paramServer_
#f
#contextNh
#nh