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::SmaccSignal < void()>
smacc::SmaccSignal < void(const ResultConstPtr &)>
function< void()>
future< int >
shared_ptr< ActionClient >
SimpleDoneCallback
SimpleFeedbackCallback
function< void(ResultConst Ptr)>
function< void(FeedbackConst Ptr)>
SimpleActiveCallback
smacc::ISmaccClientBehavior
smacc::ISmaccClient
smacc::ISmaccOrthogonal
smacc::ISmaccComponent
smacc::SignalDetector
smacc::ISmaccStateMachine
smacc::ISmaccState
smacc::introspection ::SmaccStateInfo
type_info *
std::enable_shared _from_this< SmaccStateInfo >
int
string
NodeHandle
Publisher
cl_move_base_z::odom _tracker::OdomTracker
+ OdomTracker()
+ processOdometryMessage()
+ setWorkingMode()
+ setPublishMessages()
+ pushPath()
+ popPath()
+ clearPath()
+ setStartPoint()
+ setStartPoint()
+ getPath()
+ logStateString()
+ getStackedPaths()
# reconfigCB()
# rtPublishPaths()
# updateRecordPath()
# updateClearPath()
# updateAggregatedStackPath()
cl_move_base_z::Pose
+ Pose()
+ update()
+ waitTransformUpdate()
+ toPoseMsg()
+ toPoseStampedMsg()
+ getReferenceFrame()
+ getFrameId()
smacc::ISmaccUpdatable
+ ISmaccUpdatable()
+ ISmaccUpdatable()
+ executeUpdate()
+ setUpdatePeriod()
# update()
vector< nav_msgs::Path >
CallbackType
Server< move_base_z _client_plugin::OdomTracker Config >
Path
shared_ptr< realtime _tools::RealtimePublisher < nav_msgs::Path > >
Subscriber
WorkingMode
bool
mutex
PoseStamped
shared_ptr< tf::Transform Listener >
Time
optional< ros::Duration >