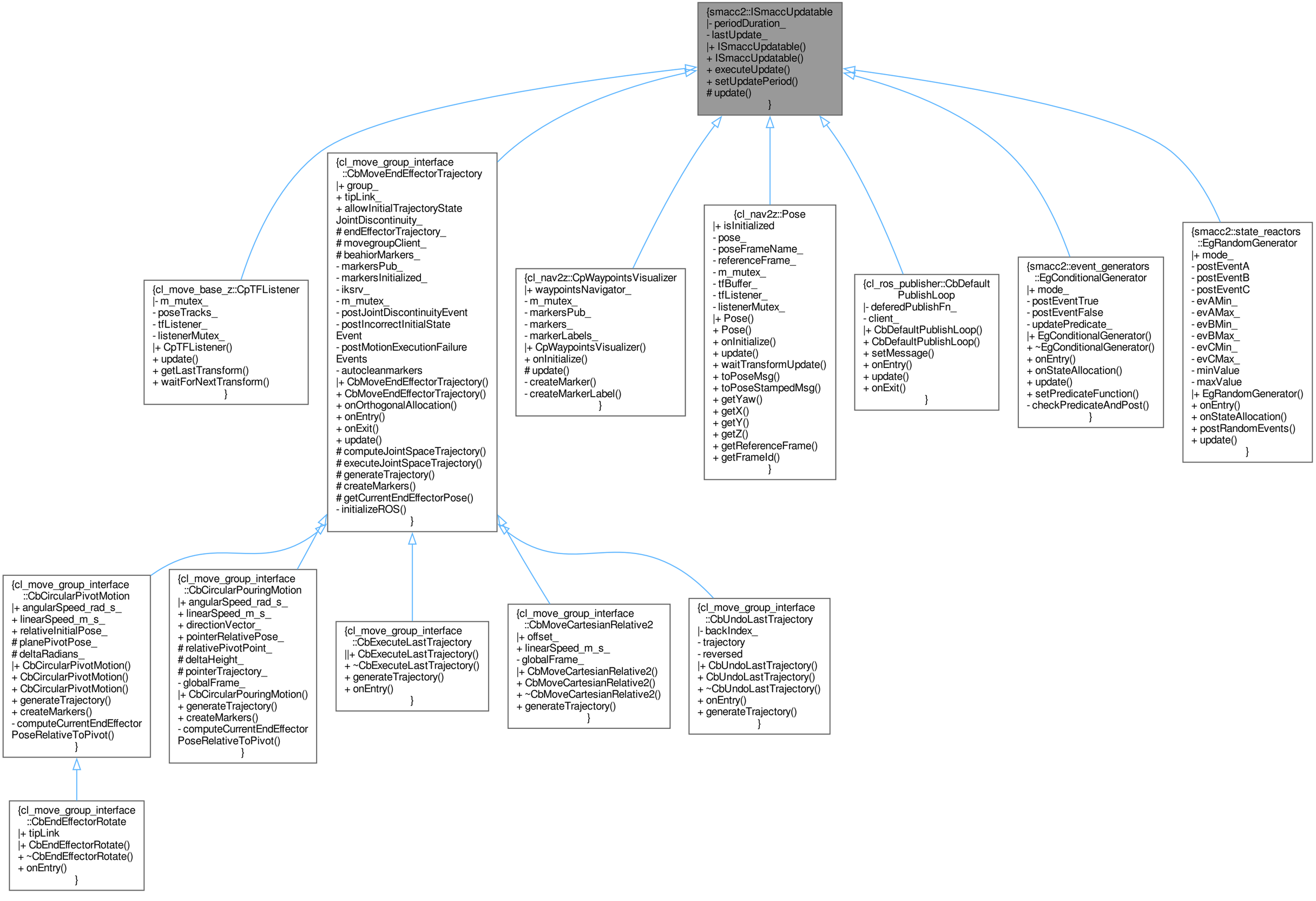
{smacc2::ISmaccUpdatable
|- periodDuration_
- lastUpdate_
|+ ISmaccUpdatable()
+ ISmaccUpdatable()
+ executeUpdate()
+ setUpdatePeriod()
# update()
}
{cl_move_base_z::CpTFListener
|- m_mutex_
- poseTracks_
- tfListener_
- listenerMutex_
|+ CpTFListener()
+ update()
+ getLastTransform()
+ waitForNextTransform()
}
{cl_move_group_interface
::CbMoveEndEffectorTrajectory
|+ group_
+ tipLink_
+ allowInitialTrajectoryState
JointDiscontinuity_
endEffectorTrajectory_
movegroupClient_
beahiorMarkers_
- markersPub_
- markersInitialized_
- iksrv_
- m_mutex_
- postJointDiscontinuityEvent
- postIncorrectInitialState
Event
- postMotionExecutionFailure
Events
- autocleanmarkers
|+ CbMoveEndEffectorTrajectory()
+ CbMoveEndEffectorTrajectory()
+ onOrthogonalAllocation()
+ onEntry()
+ onExit()
+ update()
# computeJointSpaceTrajectory()
# executeJointSpaceTrajectory()
# generateTrajectory()
# createMarkers()
# getCurrentEndEffectorPose()
- initializeROS()
}
{cl_nav2z::CpWaypointsVisualizer
|+ waypointsNavigator_
- m_mutex_
- markersPub_
- markers_
- markerLabels_
|+ CpWaypointsVisualizer()
+ onInitialize()
# update()
- createMarker()
- createMarkerLabel()
}
{cl_nav2z::Pose
|+ isInitialized
- pose_
- poseFrameName_
- referenceFrame_
- m_mutex_
- tfBuffer_
- tfListener_
- listenerMutex_
|+ Pose()
+ Pose()
+ onInitialize()
+ update()
+ waitTransformUpdate()
+ toPoseMsg()
+ toPoseStampedMsg()
+ getYaw()
+ getX()
+ getY()
+ getZ()
+ getReferenceFrame()
+ getFrameId()
}
{cl_ros_publisher::CbDefault
PublishLoop
|- deferedPublishFn_
- client_
|+ CbDefaultPublishLoop()
+ CbDefaultPublishLoop()
+ setMessage()
+ onEntry()
+ update()
+ onExit()
}
{smacc2::event_generators
::EgConditionalGenerator
|+ mode_
- postEventTrue
- postEventFalse
- updatePredicate_
|+ EgConditionalGenerator()
+ ~EgConditionalGenerator()
+ onEntry()
+ onStateAllocation()
+ update()
+ setPredicateFunction()
- checkPredicateAndPost()
}
{smacc2::state_reactors
::EgRandomGenerator
|+ mode_
- postEventA
- postEventB
- postEventC
- evAMin_
- evAMax_
- evBMin_
- evBMax_
- evCMin_
- evCMax_
- minValue
- maxValue
|+ EgRandomGenerator()
+ onEntry()
+ onStateAllocation()
+ postRandomEvents()
+ update()
}
{cl_move_group_interface
::CbCircularPivotMotion
|+ angularSpeed_rad_s_
+ linearSpeed_m_s_
+ relativeInitialPose_
# planePivotPose_
# deltaRadians_
|+ CbCircularPivotMotion()
+ CbCircularPivotMotion()
+ CbCircularPivotMotion()
+ generateTrajectory()
+ createMarkers()
- computeCurrentEndEffector
PoseRelativeToPivot()
}
{cl_move_group_interface
::CbCircularPouringMotion
|+ angularSpeed_rad_s_
+ linearSpeed_m_s_
+ directionVector_
+ pointerRelativePose_
# relativePivotPoint_
# deltaHeight_
# pointerTrajectory_
- globalFrame_
|+ CbCircularPouringMotion()
+ generateTrajectory()
+ createMarkers()
- computeCurrentEndEffector
PoseRelativeToPivot()
}
{cl_move_group_interface
::CbExecuteLastTrajectory
||+ CbExecuteLastTrajectory()
+ ~CbExecuteLastTrajectory()
+ generateTrajectory()
+ onEntry()
}
{cl_move_group_interface
::CbMoveCartesianRelative2
|+ offset_
+ linearSpeed_m_s_
- globalFrame_
|+ CbMoveCartesianRelative2()
+ CbMoveCartesianRelative2()
+ ~CbMoveCartesianRelative2()
+ generateTrajectory()
}
{cl_move_group_interface
::CbUndoLastTrajectory
|- backIndex_
- trajectory
- reversed
|+ CbUndoLastTrajectory()
+ CbUndoLastTrajectory()
+ ~CbUndoLastTrajectory()
+ onEntry()
+ generateTrajectory()
}
{cl_move_group_interface
::CbEndEffectorRotate
|+ tipLink
|+ CbEndEffectorRotate()
+ ~CbEndEffectorRotate()
+ onEntry()
}