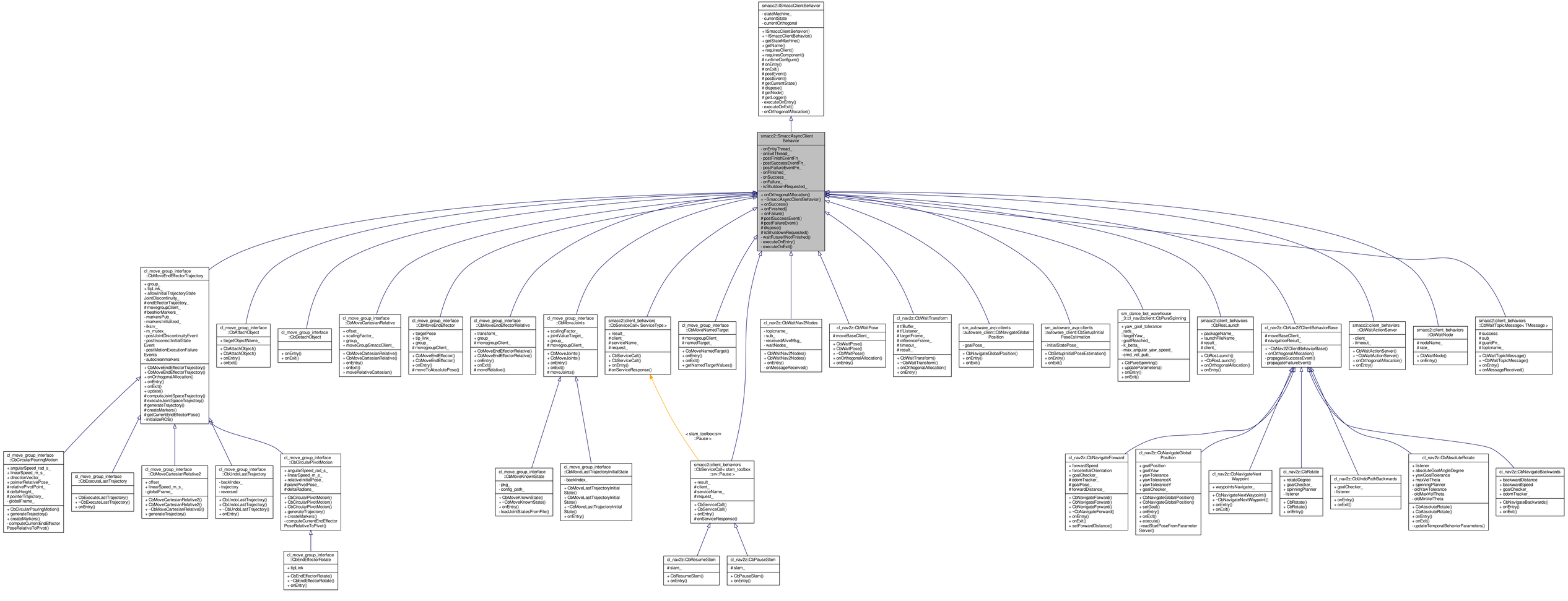
smacc2::ISmaccClientBehavior
- stateMachine_
- currentState
- currentOrthogonal
+ ISmaccClientBehavior()
+ ~ISmaccClientBehavior()
+ getStateMachine()
+ getName()
+ requiresClient()
+ requiresComponent()
# runtimeConfigure()
# onEntry()
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# postEvent()
# postEvent()
# getCurrentState()
# dispose()
# getNode()
# getLogger()
- executeOnEntry()
- executeOnExit()
- onOrthogonalAllocation()
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- postFinishEventFn_
- postSuccessEventFn_
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- onFinished_
- onSuccess_
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- isShutdownRequested_
+ onOrthogonalAllocation()
+ ~SmaccAsyncClientBehavior()
+ onSuccess()
+ onFinished()
+ onFailure()
# postSuccessEvent()
# postFailureEvent()
# dispose()
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- waitFutureIfNotFinished()
- executeOnEntry()
- executeOnExit()
cl_move_group_interface ::ClbMoveEndEffectorTrajectory
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+ tipLink_
+ allowInitialTrajectoryState JointDiscontinuity_
# endEffectorTrajectory_
# movegroupClient_
# beahioMarkers_
- markersPub_
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- posJointDiscontinuityEvent
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- autoclearnmarkers
+ ClbMoveEndEffectorTrajectory()
+ ClbMoveEndEffectorTrajectory()
+ onOrthogonalAllocation()
+ onEntry()
+ onExit()
+ update()
# computeJointSpaceTrajectory()
# executeJointSpaceTrajectory()
# generateTrajectory()
# createMarkers()
# getCurrentEndEffectorPose()
- initializeROS()
cl_move_group_interface ::ClbAttachObject
+ targetObjectName_
+ ClbAttachObject()
+ ClbAttachObject()
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cl_move_group_interface ::ClbDetachObject
+ onEntry()
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cl_move_group_interface ::ClbMoveCartesianRelative
+ offset_
+ scalingFactor_
+ group_
+ moveGroupSmaccClient_
+ ClbMoveCartesianRelative()
+ ClbMoveCartesianRelative()
+ onEntry()
+ onExit()
# moveRelativeCartesian()
cl_move_group_interface ::ClbMoveEndEffector
+ targetPose
+ tip_link_
+ group_
# movegroupClient_
+ ClbMoveEndEffector()
+ ClbMoveEndEffector()
+ onEntry()
# moveToAbsolutePose()
cl_move_group_interface ::ClbMoveEndEffectorRelative
+ transform_
+ group_
# movegroupClient_
+ ClbMoveEndEffectorRelative()
+ ClbMoveEndEffectorRelative()
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# moveRelative()
cl_move_group_interface ::ClbMoveJoints
+ scalingFactor_
+ jointValueTarget_
+ group_
# movegroupClient_
+ ClbMoveJoints()
+ ClbMoveJoints()
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# moveJoints()
smacc2::client_behaviors ::CbServiceCall< ServiceType >
+ result_
# client_
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+ CbServiceCall()
+ CbServiceCall()
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cl_move_group_interface ::CbMoveNamedTarget
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+ CbMoveNamedTarget()
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+ onExit()
+ getNamedTargetValues()
cl_nav2z::CbWaitNav2Nodes
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- onMessageReceived()
cl_nav2z::CbWaitPose
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+ CbWaitPose()
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cl_nav2z::CbWaitTransform
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+ CbWaitTransform()
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sm_autoware_avp::clients :autoware_client::CbNavigateGlobal Position
- goalPose_
+ CbNavigateGlobalPosition()
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sm_autoware_avp::clients :autoware_client::CbSetupInitial PoseEstimation
- initialStatePose_
+ CbSetupInitialPoseEstimation()
+ onEntry()
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sm_dance_bot_warehouse _3::cl_nav2client::CbPureSpinning
+ yaw_goal_tolerance _rads_
- targetYaw_
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- k_betta_
- max_angular_yaw_speed_
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+ CbPureSpinning()
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smacc2::client_behaviors ::CbRosLaunch
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+ launchFileName_
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cl_nav2z::CbNav2ZClientBehaviorBase
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smacc2::client_behaviors ::CbWaitActionServer
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+ CbWaitActionServer()
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smacc2::client_behaviors ::CbWaitNode
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smacc2::client_behaviors ::CbWaitTopicMessage< TMessage >
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+ CbWaitTopicMessage()
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cl_move_group_interface ::CbCircularPouringMotion
+ angularSpeed_rad_s_
+ linearSpeed_m_s_
- directionVector_
+ pointerRelativePose_
# relativePivotPoint_
# deltaHeight_
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- globalFrame_
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+ generateTrajectory()
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cl_move_group_interface ::CbExecuteLastTrajectory
+ CbExecuteLastTrajectory()
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cl_move_group_interface ::CbMoveCartesianRelative2
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+ CbMoveCartesianRelative2()
+ CbMoveCartesianRelative2()
+ ~CbMoveCartesianRelative2()
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cl_move_group_interface ::CbUndoLastTrajectory
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- trajectory
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+ CbUndoLastTrajectory()
+ CbUndoLastTrajectory()
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cl_move_group_interface ::CbCircularPivotMotion
+ angularSpeed_rad_s_
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+ relativeInitialPose_
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+ CbCircularPivotMotion()
+ CbCircularPivotMotion()
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cl_move_group_interface ::CbMoveKnownState
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cl_move_group_interface ::CbMoveLastTrajectoryInitialState
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smacc2::client_behaviors ::CbServiceCall< slam_toolbox ::srv::Pause >
+ result_
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+ CbResumeSlam()
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cl_nav2z::CbNavigateForward
+ forwardSpeed
+ forceInitialOrientation
+ goalChecker_
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+ CbNavigateForward()
+ CbNavigateForward()
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+ onEntry()
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+ goalPosition
+ goalYaw
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+ execute()
- readStartPoseFromParameter Server()
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+ waypointsNavigator_
+ CbNavigateNextWaypoint()
+ ~CbNavigateNextWaypoint()
+ onEntry()
+ onExit()
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+ rotateDegree
+ goalChecker_
+ spinningPlanner
- listener
+ CbRotate()
+ CbRotate()
+ onEntry()
cl_nav2z::CbUndoPathBackwards
+ goalChecker_
- listener
+ onEntry()
+ onExit()
cl_nav2z::CbAbsoluteRotate
+ listener
+ absoluteGoalAngleDegree
+ yawGoalTolerance
+ maxVelTheta
+ spinningPlanner
- oldYawTolerance
- oldMaxVelTheta
- oldMinVelTheta
+ CbAbsoluteRotate()
+ CbAbsoluteRotate()
+ onEntry()
+ onExit()
- updateTemporalBehaviorParameters()
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+ backwardDistance
+ backwardSpeed
+ goalChecker_
+ odomTracker_
+ CbNavigateBackwards()
+ onEntry()
+ onExit()