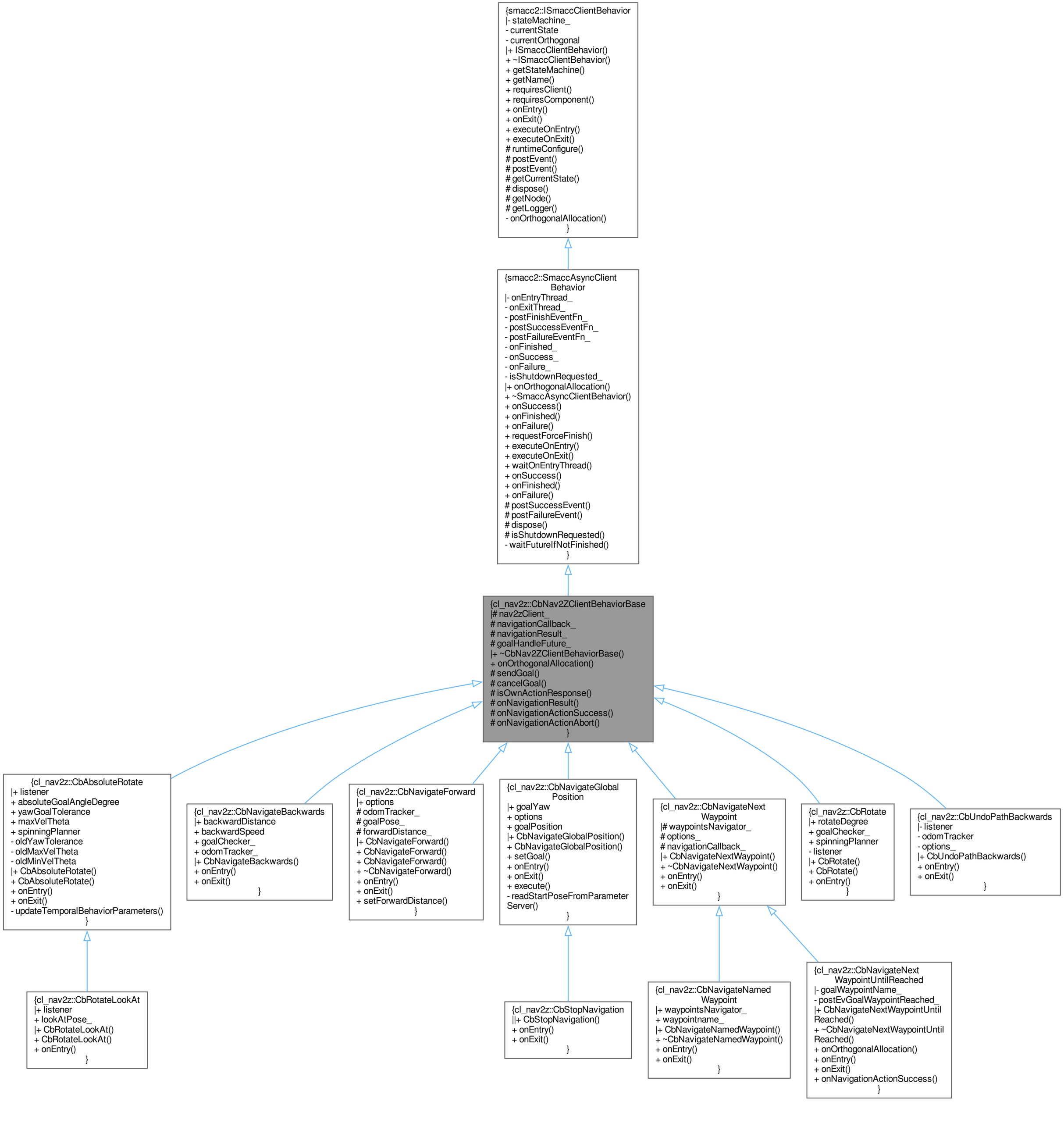
{smacc2::ISmaccClientBehavior
|- stateMachine_
- currentState
- currentOrthogonal
|+ ISmaccClientBehavior()
+ ~ISmaccClientBehavior()
+ getStateMachine()
+ getName()
+ requiresClient()
+ requiresComponent()
+ onEntry()
+ onExit()
+ executeOnEntry()
+ executeOnExit()
# runtimeConfigure()
# postEvent()
# postEvent()
# getCurrentState()
# dispose()
# getNode()
# getLogger()
- onOrthogonalAllocation()
}
{smacc2::SmaccAsyncClient Behavior
|- onEntryThread_
- onExitThread_
- postFinishEventFn_
- postSuccessEventFn_
- postFailureEventFn_
- onFinished_
- onSuccess_
- onFailure_
- isShutdownRequested_
|+ onOrthogonalAllocation()
+ ~SmaccAsyncClientBehavior()
+ onSuccess()
+ onFinished()
+ onFailure()
+ requestForceFinish()
+ executeOnEntry()
+ executeOnExit()
+ waitOnEntryThread()
+ onSuccess()
+ onFinished()
+ onFailure()
# postSuccessEvent()
# postFailureEvent()
# dispose()
# isShutdownRequested()
- waitFutureIfNotFinished()
}
{cl_nav2z::CbNav2ZClientBehaviorBase
|# nav2zClient_
navigationCallback_
navigationResult_
goalHandleFuture_
|+ ~CbNav2ZClientBehaviorBase()
+ onOrthogonalAllocation()
# sendGoal()
# cancelGoal()
# isOwnActionResponse()
# onNavigationResult()
# onNavigationActionSuccess()
# onNavigationActionAbort()
}
{cl_nav2z::CbAbsoluteRotate
|+ listener
+ absoluteGoalAngleDegree
+ yawGoalTolerance
+ maxVelTheta
+ spinningPlanner
- oldYawTolerance
- oldMaxVelTheta
- oldMinVelTheta
|+ CbAbsoluteRotate()
+ CbAbsoluteRotate()
+ onEntry()
+ onExit()
- updateTemporalBehaviorParameters()
}
{cl_nav2z::CbNavigateBackwards
|+ backwardDistance
+ backwardSpeed
+ goalChecker_
+ odomTracker_
|+ CbNavigateBackwards()
+ onEntry()
+ onExit()
}
{cl_nav2z::CbNavigateForward
|+ options
odomTracker_
goalPose_
forwardDistance_
|+ CbNavigateForward()
+ CbNavigateForward()
+ CbNavigateForward()
+ ~CbNavigateForward()
+ onEntry()
+ onExit()
+ setForwardDistance()
}
{cl_nav2z::CbNavigateGlobal Position
|+ goalYaw
+ options
+ goalPosition
|+ CbNavigateGlobalPosition()
+ CbNavigateGlobalPosition()
+ setGoal()
+ onEntry()
+ onExit()
+ execute()
- readStartPoseFromParameter Server()
}
{cl_nav2z::CbNavigateNext Waypoint
|# waypointsNavigator_
options_
navigationCallback_
|+ CbNavigateNextWaypoint()
+ ~CbNavigateNextWaypoint()
+ onEntry()
+ onExit()
}
{cl_nav2z::CbRotate
|+ rotateDegree
+ goalChecker_
+ spinningPlanner
- listener
|+ CbRotate()
+ CbRotate()
+ onEntry()
}
{cl_nav2z::CbUndoPathBackwards
|- listener
- odomTracker
- options_
|+ CbUndoPathBackwards()
+ onEntry()
+ onExit()
}
{cl_nav2z::CbRotateLookAt
|+ listener
+ lookAtPose_
|+ CbRotateLookAt()
+ CbRotateLookAt()
+ onEntry()
}
{cl_nav2z::CbStopNavigation
||+ CbStopNavigation()
+ onEntry()
+ onExit()
}
{cl_nav2z::CbNavigateNamed Waypoint
|+ waypointsNavigator_
+ waypointname_
|+ CbNavigateNamedWaypoint()
+ ~CbNavigateNamedWaypoint()
+ onEntry()
+ onExit()
}
{cl_nav2z::CbNavigateNext WaypointUntilReached
|- goalWaypointName_
- postEvGoalWaypointReached_
|+ CbNavigateNextWaypointUntil Reached()
+ ~CbNavigateNextWaypointUntil Reached()
+ onOrthogonalAllocation()
+ onEntry()
+ onExit()
+ onNavigationActionSuccess()
}