{smacc2::ISmaccComponent
|# stateMachine_
owner_
|+ ISmaccComponent()
+ ~ISmaccComponent()
+ getName()
# onInitialize()
# postEvent()
# postEvent()
# onOrthogonalAllocation()
# requiresComponent()
# requiresComponent()
# requiresClient()
# createSiblingComponent()
# createSiblingNamedComponent()
# getNode()
# getLogger()
# getStateMachine()
- initialize()
- setStateMachine()
}
{cl_nav2z::odom_tracker
::OdomTracker
|# robotBasePathPub_
robotBasePathStackedPub_
odomSub_
recordPointDistanceThreshold_
recordAngularDistanceThreshold_
clearPointDistanceThreshold_
clearAngularDistanceThreshold_
odomFrame_
odomTopicName_
publishMessages
baseTrajectory_
workingMode_
pathStack_
pathInfos_
aggregatedStackPathMsg_
subscribeToOdometryTopic_
currentMotionGoal_
currentPathName_
m_mutex_
|+ OdomTracker()
+ processOdometryMessage()
+ setWorkingMode()
+ setPublishMessages()
+ pushPath()
+ pushPath()
+ popPath()
+ clearPath()
+ setStartPoint()
+ setStartPoint()
+ setCurrentMotionGoal()
+ setCurrentPathName()
+ getCurrentMotionGoal()
+ getPath()
+ logStateString()
# onInitialize()
# updateConfiguration()
# rtPublishPaths()
# updateRecordPath()
# updateClearPath()
# updateAggregatedStackPath()
}