smacc2::ISmaccClientBehavior

- stateMachine_
- currentState
- currentOrthogonal

+ ISmaccClientBehavior()
+ ~ISmaccClientBehavior()
+ getStateMachine()
+ getName()
+ requiresClient()
+ requiresComponent()
+ onEntry()
+ onExit()
+ executeOnEntry()
+ executeOnExit()
# runtimeConfigure()
# postEvent()
# postEvent()
# getCurrentState()
# dispose()
# getNode()
# getLogger()
- onOrthogonalAllocation()

cl_nav2z::CbSeekWaypoint

+ waypointsNavigator_
+ options_
- count_
- seekWaypointName_

+ CbSeekWaypoint()
+ ~CbSeekWaypoint()
+ onEntry()
+ onExit()

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()

smacc2::SmaccClientBehavior

+ onEntry()
+ onExit()

smacc2::client_behaviors
::CbServiceCall< slam_toolbox
::srv::Pause >

+ result_
# client_
# serviceName_
# request_

+ CbServiceCall()
+ CbServiceCall()
+ onEntry()
# onServiceResponse()

cl_move_group_interface
::CbAttachObject

+ targetObjectName_

+ CbAttachObject()
+ CbAttachObject()
+ onEntry()
+ onExit()

cl_move_group_interface
::CbDetachObject

+ onEntry()
+ onExit()

cl_move_group_interface
::CbMoveCartesianRelative

+ offset_
+ scalingFactor_
+ group_
+ moveGroupSmaccClient_

+ CbMoveCartesianRelative()
+ CbMoveCartesianRelative()
+ onEntry()
+ onExit()
+ moveRelativeCartesian()

cl_move_group_interface
::CbMoveEndEffector

+ targetPose
+ tip_link_
+ group_
# movegroupClient_

+ CbMoveEndEffector()
+ CbMoveEndEffector()
+ onEntry()
# moveToAbsolutePose()

cl_move_group_interface
::CbMoveEndEffectorRelative

+ transform_
+ group_
# movegroupClient_

+ CbMoveEndEffectorRelative()
+ CbMoveEndEffectorRelative()
+ onEntry()
+ onExit()
# moveRelative()

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_move_group_interface
::CbMoveJoints

+ scalingFactor_
+ jointValueTarget_
+ group_
# movegroupClient_

+ CbMoveJoints()
+ CbMoveJoints()
+ onEntry()
+ onExit()
# moveJoints()

cl_move_group_interface
::CbMoveNamedTarget

movegroupClient_
namedTarget_

+ CbMoveNamedTarget()
+ onEntry()
+ onExit()
+ getNamedTargetValues()

cl_move_group_interface
::CbWaitJointState

- triggered
- mutex

- sub_

+ CbWaitJointState()
+ onEntry()
- onMessageReceived()

cl_nav2z::CbNav2ZClientBehaviorBase

nav2zClient_
navigationResult_
goalHandleFuture_

+ ~CbNav2ZClientBehaviorBase()
+ onOrthogonalAllocation()
# sendGoal()
# isOwnActionResponse()
# onNavigationActionSuccess()
# onNavigationActionAbort()

cl_nav2z::CbWaitNav2Nodes

- topicname_
- sub_
- receivedAliveMsg_
- waitNodes_

+ CbWaitNav2Nodes()
+ CbWaitNav2Nodes()
+ onEntry()
- onMessageReceived()

cl_nav2z::CbWaitPose

nav2zClient_

+ CbWaitPose()
+ CbWaitPose()
+ ~CbWaitPose()
+ onOrthogonalAllocation()
+ onEntry()

cl_nav2z::CbWaitTransform

tfBuffer_
tfListener_
targetFrame_
referenceFrame_
timeout_
result_

+ CbWaitTransform()
+ ~CbWaitTransform()
+ onOrthogonalAllocation()
+ onEntry()

sm_autoware_avp::clients
::autoware_client::CbNavigateGlobal
Position

- goalPose_

+ CbNavigateGlobalPosition()
+ onEntry()
+ onExit()

sm_autoware_avp::clients
::autoware_client::CbSetupInitial
PoseEstimation

- initialStatePose_

+ CbSetupInitialPoseEstimation()
+ onEntry()
+ onExit()

sm_dance_bot_warehouse
_3::cl_nav2zclient::CbPureSpinning

+ yaw_goal_tolerance
rads
- targetYaw_
- goalReached_
- k_betta_
- max_angular_yaw_speed_
- cmd_vel_pub_

+ CbPureSpinning()
+ updateParameters()
+ onEntry()
+ onExit()

sm_husky_barrel_search
_1::CbSleepFor

- sleeptime_

+ CbSleepFor()
+ onEntry()
+ onExit()

sm_husky_barrel_search
_1::cl_led_array::CbBlinking

+ color_

+ CbBlinking()
+ onEntry()
+ onExit()

sm_husky_barrel_search
_1::cl_led_array::CbSequence
ColorBlinking

+ onEntry()
+ onExit()

smacc2::client_behaviors
::CbRosLaunch

+ packageName_
+ launchFileName_
# result_
# client_

+ CbRosLaunch()
+ ~CbRosLaunch()
+ onOrthogonalAllocation()
+ onEntry()

smacc2::client_behaviors
::CbSequence

- sequenceNodes_
- conn_
- conn2_
- bh_
- consume_

+ CbSequence()
+ onEntry()
+ onExit()
+ then()
- onSubNodeSuccess()
- onSubNodeAbort()
- recursiveConsumeNext()

smacc2::client_behaviors
::CbServiceCall< ServiceType >

+ result_
# client_
# serviceName_
# request_

+ CbServiceCall()
+ CbServiceCall()
+ onEntry()
# onServiceResponse()

smacc2::client_behaviors
::CbWaitActionServer

- client_
- timeout_

+ CbWaitActionServer()
+ ~CbWaitActionServer()
+ onOrthogonalAllocation()
+ onEntry()

smacc2::client_behaviors
::CbWaitNode

nodeName_
rate_

+ CbWaitNode()
+ onEntry()

smacc2::client_behaviors
::CbWaitTopicMessage< TMessage >

success
sub_
guardFn_
topicname_

+ CbWaitTopicMessage()
+ ~CbWaitTopicMessage()
+ onEntry()
+ onMessageReceived()

cl_nav2z::CbPauseSlam

slam_

+ CbPauseSlam()
+ onEntry()

cl_nav2z::CbResumeSlam

slam_

+ CbResumeSlam()
+ onEntry()

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()

cl_move_group_interface
::CbMoveKnownState

- pkg_
- config_path_

+ CbMoveKnownState()
+ ~CbMoveKnownState()
+ onEntry()
- loadJointStatesFromFile()

cl_move_group_interface
::CbMoveLastTrajectoryInitialState

- backIndex_

+ CbMoveLastTrajectoryInitial
State()
+ CbMoveLastTrajectoryInitial
State()
+ ~CbMoveLastTrajectoryInitial
State()
+ onEntry()

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_

+ CbNavigateNextWaypoint()
+ ~CbNavigateNextWaypoint()
+ onEntry()
+ onExit()

cl_nav2z::CbRotate

+ rotateDegree
+ goalChecker_
+ spinningPlanner
- listener

+ CbRotate()
+ CbRotate()
+ onEntry()

cl_nav2z::CbUndoPathBackwards

+ goalChecker_
- listener

+ onEntry()
+ onExit()

cl_nav2z::CbRotateLookAt

+ listener
+ lookAtPose_

+ CbRotateLookAt()
+ CbRotateLookAt()
+ onEntry()

cl_nav2z::CbNavigateNamed
Waypoint

+ waypointsNavigator_
+ waypointname_

+ CbNavigateNamedWaypoint()
+ ~CbNavigateNamedWaypoint()
+ onEntry()
+ onExit()

cl_nav2z::CbNavigateNext
WaypointUntilReached

- goalWaypointName_
- postEvGoalWaypointReached_

+ CbNavigateNextWaypointUntil
Reached()
+ ~CbNavigateNextWaypointUntil
Reached()
+ onOrthogonalAllocation()
+ onEntry()
+ onExit()
+ onNavigationActionSuccess()

< slam_toolbox::srv
::Pause >

cl_multirole_sensor
::CbDefaultMultiRoleSensor
Behavior< ClLidarSensor >

+ sensor_

+ deferedEventPropagation

+ CbDefaultMultiRoleSensor
Behavior()
+ onOrthogonalAllocation()
+ propagateEvent()
+ propagateEvent2()
+ onEntry()
+ onExit()
+ onMessageCallback()
+ getEventLabel()

cl_multirole_sensor
::CbDefaultMultiRoleSensor
Behavior< ClTemperatureSensor >

+ sensor_

+ deferedEventPropagation

+ CbDefaultMultiRoleSensor
Behavior()
+ onOrthogonalAllocation()
+ propagateEvent()
+ propagateEvent2()
+ onEntry()
+ onExit()
+ onMessageCallback()
+ getEventLabel()

cl_keyboard::CbDefaultKeyboard
Behavior

+ ClKeyboard_
+ postEventKeyPress

+ onEntry()
+ onOrthogonalAllocation()
+ OnKeyPress()
+ postKeyEvent()

cl_multirole_sensor
::CbDefaultMultiRoleSensor
Behavior< ClientType >

+ sensor_

+ deferedEventPropagation

+ CbDefaultMultiRoleSensor
Behavior()
+ onOrthogonalAllocation()
+ propagateEvent()
+ propagateEvent2()
+ onEntry()
+ onExit()
+ onMessageCallback()
+ getEventLabel()

cl_ros_publisher::CbDefault
PublishLoop

- deferedPublishFn_
- client_

+ CbDefaultPublishLoop()
+ CbDefaultPublishLoop()
+ setMessage()
+ onEntry()
+ update()
+ onExit()

cl_ros_publisher::CbMuted
Behavior< RosMsgType >

+ onEntry()
+ onExit()

cl_ros_publisher::CbPublish
Once< RosMsgType >

- deferedPublishFn
- client_

+ CbPublishOnce()
+ CbPublishOnce()
+ setMessage()
+ onEntry()
+ onExit()

cl_ros_timer::CbTimer

- timerClient_
- postTimerEvent_
- c_

+ onEntry()
+ onEntry()
+ onOrthogonalAllocation()
+ onClientTimerTickCallback()
+ onEntry()
+ onExit()
+ onOrthogonalAllocation()
+ onClientTimerTickCallback()

cl_ros_timer::CbTimerCountdownLoop

- tickTriggerCount_
- tickCounter_
- timerClient_
- postCountDownEvent_
- onTimerTick_

+ CbTimerCountdownLoop()
+ onEntry()
+ onEntry()
+ onOrthogonalAllocation()
+ onTimerTick()
+ CbTimerCountdownLoop()
+ onEntry()
+ onExit()
+ onOrthogonalAllocation()
+ onTimerTick()
- onClientTimerTickCallback()
- onClientTimerTickCallback()

cl_ros_timer::CbTimerCountdownOnce

- tickCounter_
- tickTriggerCount_
- timerClient_
- postCountDownEvent_
- onTimerTick_

+ CbTimerCountdownOnce()
+ onEntry()
+ onEntry()
+ onOrthogonalAllocation()
+ onTimerTick()
+ CbTimerCountdownOnce()
+ onEntry()
+ onExit()
+ onOrthogonalAllocation()
+ onTimerTick()
- onClientTimerTickCallback()
- onClientTimerTickCallback()

sm_advanced_recovery
_1::cl_subscriber::CbDefault
SubscriberBehavior

+ onEntry()

sm_advanced_recovery
_1::cl_subscriber::CbWatchdog
SubscriberBehavior

+ onEntry()

sm_dance_bot::cl_led
::CbLEDOff

+ ledActionClient_

+ onEntry()
+ onExit()

sm_dance_bot::cl_led
::CbLEDOn

+ ledActionClient_

+ onEntry()
+ onExit()

sm_dance_bot::cl_service3
::CbService3

- serviceClient_
- value_

+ CbService3()
+ onEntry()

sm_dance_bot::cl_string
_publisher::CbStringPublisher

+ publisherClient_
+ msg_

+ CbStringPublisher()
+ runtimeConfigure()
+ onEntry()
+ onExit()

sm_dance_bot_strikes
_back::cl_led::CbLEDOff

+ ledActionClient_

+ onEntry()
+ onExit()

sm_dance_bot_strikes
_back::cl_led::CbLEDOn

+ ledActionClient_

+ onEntry()
+ onExit()

sm_dance_bot_strikes
_back::cl_service3::CbService3

- serviceClient_
- value_

+ CbService3()
+ onEntry()

sm_dance_bot_strikes
_back::cl_string_publisher
::CbStringPublisher

+ publisherClient_
+ msg_

+ CbStringPublisher()
+ runtimeConfigure()
+ onEntry()
+ onExit()

sm_dance_bot_warehouse
::cl_led::CbLEDOff

+ ledActionClient_

+ onEntry()
+ onExit()

sm_dance_bot_warehouse
::cl_led::CbLEDOn

+ ledActionClient_

+ onEntry()
+ onExit()

sm_dance_bot_warehouse
::cl_service3::CbService3

- serviceClient_
- value_

+ CbService3()
+ onEntry()

sm_dance_bot_warehouse
::cl_string_publisher
::CbStringPublisher

+ publisherClient_
+ msg_

+ CbStringPublisher()
+ runtimeConfigure()
+ onEntry()
+ onExit()

sm_dance_bot_warehouse
_2::cl_led::CbLEDOff

+ ledActionClient_

+ onEntry()
+ onExit()

sm_dance_bot_warehouse
_2::cl_led::CbLEDOn

+ ledActionClient_

+ onEntry()
+ onExit()

sm_dance_bot_warehouse
_2::cl_service3::CbService3

- serviceClient_
- value_

+ CbService3()
+ onEntry()

sm_dance_bot_warehouse
_2::cl_string_publisher
::CbStringPublisher

+ publisherClient_
+ msg_

+ CbStringPublisher()
+ runtimeConfigure()
+ onEntry()
+ onExit()

sm_dance_bot_warehouse
_3::cl_led::CbLEDOff

+ ledActionClient_

+ onEntry()
+ onExit()

sm_dance_bot_warehouse
_3::cl_led::CbLEDOn

+ ledActionClient_

+ onEntry()
+ onExit()

sm_dance_bot_warehouse
_3::cl_service3::CbService3

- serviceClient_
- value_

+ CbService3()
+ onEntry()

sm_dance_bot_warehouse
_3::cl_string_publisher
::CbStringPublisher

+ publisherClient_
+ msg_

+ CbStringPublisher()
+ runtimeConfigure()
+ onEntry()
+ onExit()

sm_ferrari::cl_subscriber
::CbMySubscriberBehavior

+ postMyEvent_

+ onEntry()
+ onOrthogonalAllocation()
+ onMessageReceived()

sm_husky_barrel_search
_1::cl_led_array::CbLEDOff

+ color_

+ CbLEDOff()
+ onEntry()
+ onExit()

sm_husky_barrel_search
_1::cl_led_array::CbLEDOn

+ color_

+ CbLEDOn()
+ onEntry()
+ onExit()

sm_multi_stage_1::cl
_subscriber::CbDefaultSubscriber
Behavior

+ onEntry()

sm_multi_stage_1::cl
_subscriber::CbWatchdogSubscriber
Behavior

+ onEntry()

sm_pack_ml::cl_subscriber
::CbDefaultSubscriberBehavior

+ onEntry()

sm_pack_ml::cl_subscriber
::CbWatchdogSubscriberBehavior

+ onEntry()

sm_pubsub_1::cl_subscriber
::CbMySubscriberBehavior

+ postMyEvent_

+ onEntry()
+ onOrthogonalAllocation()
+ onMessageReceived()

sm_respira_1::cl_subscriber
::CbDefaultSubscriberBehavior

+ onEntry()

sm_respira_1::cl_subscriber
::CbWatchdogSubscriberBehavior

+ onEntry()

sm_three_some::cl_subscriber
::CbDefaultSubscriberBehavior

+ onEntry()

sm_three_some::cl_subscriber
::CbWatchdogSubscriberBehavior

+ onEntry()

smacc2::client_behaviors
::CbSubscriptionCallbackBase
< TMsg >

attachedClient_

+ onEntry()
+ onMessageReceived()

sm_dance_bot::cl_lidar
::CbLidarSensor

+ CbLidarSensor()
+ onEntry()
+ onMessageCallback()

sm_dance_bot_strikes
_back::cl_lidar::CbLidarSensor

+ CbLidarSensor()
+ onEntry()
+ onMessageCallback()

sm_dance_bot_warehouse
::cl_lidar::CbLidarSensor

+ CbLidarSensor()
+ onEntry()
+ onMessageCallback()

sm_dance_bot_warehouse
_2::cl_lidar::CbLidarSensor

+ CbLidarSensor()
+ onEntry()
+ onMessageCallback()

sm_dance_bot_warehouse
_3::cl_lidar::CbLidarSensor

+ CbLidarSensor()
+ onEntry()
+ onMessageCallback()

sm_dance_bot::cl_temperature
_sensor::CbConditionTemperatureSensor

+ CbConditionTemperatureSensor()
+ onEntry()
+ onMessageCallback()

sm_dance_bot_strikes
_back::cl_temperature
_sensor::CbConditionTemperature
Sensor

+ CbConditionTemperatureSensor()
+ onEntry()
+ onMessageCallback()

sm_dance_bot_warehouse
::cl_temperature_sensor
::CbConditionTemperatureSensor

+ CbConditionTemperatureSensor()
+ onEntry()
+ onMessageCallback()

sm_dance_bot_warehouse
_2::cl_temperature_sensor
::CbConditionTemperatureSensor

+ CbConditionTemperatureSensor()
+ onEntry()
+ onMessageCallback()

sm_dance_bot_warehouse
_3::cl_temperature_sensor
::CbConditionTemperatureSensor

+ CbConditionTemperatureSensor()
+ onEntry()
+ onMessageCallback()

< ClLidarSensor > < ClTemperatureSensor >