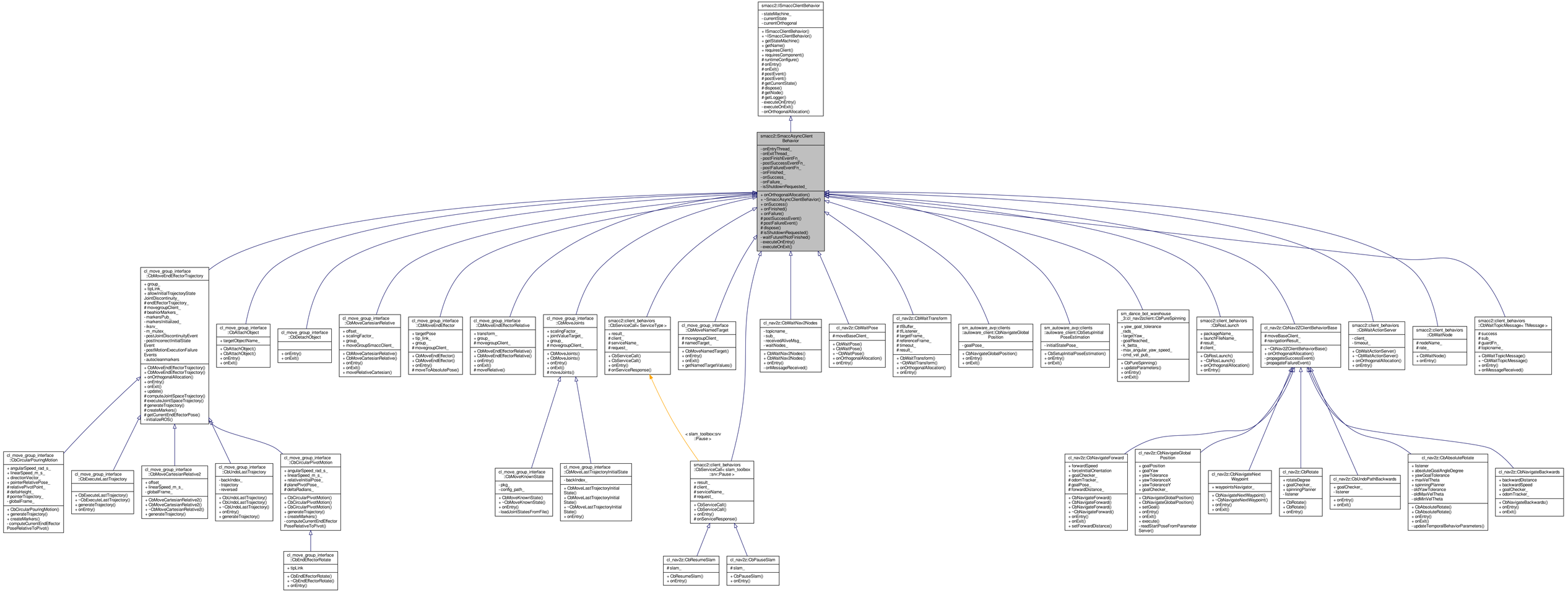
smacc2::ISmaccClientBehavior
- stateMachine_
- currentState
- currentOrthogonal
+ ISmaccClientBehavior()
+ ~ISmaccClientBehavior()
+ getStateMachine()
+ getName()
+ requiresClient()
+ requiresComponent()
# runtimeConfigure()
# onEntry()
# onExit()
# postEvent()
# postEvent()
# getCurrentState()
# dispose()
# getNode()
# getLogger()
- executeOnEntry()
- executeOnExit()
- onOrthogonalAllocation()
smacc2::SmaccAsyncClientBehavior
- onEntryThread_
- onExitThread_
- postFinishEventFn_
- postSuccessEventFn_
- postFailureEventFn_
- onFinished_
- onSuccess_
- onFailure
- isShutdownRequested_
+ onOrthogonalAllocation()
+ ~SmaccAsyncClientBehavior()
+ onSuccess()
+ onFinished()
+ onFailure()
# postSuccessEvent()
# postFailureEvent()
# dispose()
# isShutdownRequested()
- waitFutureIfNotFinished()
- executeOnEntry()
- executeOnExit()
cl_move_group_interface ::CbMoveEndEffectorTrajectory
+ group_
+ tipLink_
+ allowInitialTrajectoryState JointDiscontinuity_
# endEffectorTrajectory_
# movegroupClient_
# beaharMarkers_
- 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 ::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 ::CbMoveJoints
+ scalingFactor_
+ jointValueTarget_
+ group_
# movegroupClient_
+ CbMoveJoints()
+ CbMoveJoints()
+ onEntry()
+ onExit()
# moveJoints()
smacc2::client_behaviors ::CbServiceCall< ServiceType >
+ result_
# client_
# serviceName_
# request_
+ CbServiceCall()
+ CbServiceCall()
+ onEntry()
# onServiceResponse()
cl_move_group_interface ::CbMoveNamedTarget
movegroupClient_
namedTarget_
+ CbMoveNamedTarget()
+ onEntry()
+ onExit()
+ getNamedTargetValues()
cl_nav2z::CbWaitNavN2Nodes
- topicname_
- sub_
- receivedAliveMsg_
- waitNodes_
+ CbWaitNavN2Nodes()
+ CbWaitNavN2Nodes()
+ onEntry()
- onMessageReceived()
cl_nav2z::CbWaitPose
moveBaseClient_
+ 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_nav2client::CbPureSpinning
+ yaw_goal_tolerance
- rads_
- targetYaw_
- goalReached_
- k_betta_
- max_angular_yaw_speed_
- cmd_vel_put_
+ CbPureSpinning()
+ updateParameters()
+ onEntry()
+ onExit()
smacc2::client_behaviors ::CbRosLaunch
+ packageName_
+ launchFileName_
# result_
# client_
+ CbRosLaunch()
+ ~CbRosLaunch()
+ onOrthogonalAllocation()
+ onEntry()
cl_nav2z::CbNav2ZClientBehaviorBase
moveBaseClient_
navigationResult_
+ ~CbNav2ZClientBehaviorBase()
+ onOrthogonalAllocation()
- propagateSuccessEvent()
- propagateFailureEvent()
smacc2::client_behaviors ::CbWaitActionServer
- client_
- timeout_
+ CbWaitActionServer()
+ ~CbWaitActionServer()
+ onOrthogonalAllocation()
+ onEntry()
smacc2::client_behaviors ::CbWaitNode
nodeName_
rate_
+ CbWaitNode()
+ onEntry()
smacc2::client_behaviors ::CbWaitTopicMessage< TMessage >
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sub_
guardFn_
topicname_
+ CbWaitTopicMessage()
+ ~CbWaitTopicMessage()
+ onEntry()
+ onMessageReceived()
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 ::CbCircularPivotMotion
+ angularSpeed_rad_s_
+ linearSpeed_m_s_
+ relativeInitialPose_
# planePivotPose_
# deltaRadians_
+ CbCircularPivotMotion()
+ CbCircularPivotMotion()
+ CbCircularPivotMotion()
+ generateTrajectory()
+ createMarkers()
- computeCurrentEndEffector PoseRelativeToPivot()
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()
< slam_toolbox::srv ::Pause >
smacc2::client_behaviors ::CbServiceCall< slam_toolbox ::srv::Pause >
+ result_
# client_
# serviceName_
# request_
+ CbServiceCall()
+ CbServiceCall()
+ onEntry()
# onServiceResponse()
cl_nav2z::CbResumeSlam
slam_
+ CbResumeSlam()
+ onEntry()
cl_nav2z::CbPauseSlam
slam_
+ CbPauseSlam()
+ onEntry()
cl_nav2z::CbNavigateForward
+ forwardSpeed
+ forceInitialOrientation
+ goalChecker_
# odomTracker_
# goalPose_
# forwardDistance_
+ CbNavigateForward()
+ CbNavigateForward()
+ CbNavigateForward()
+ ~CbNavigateForward()
+ onEntry()
+ onExit()
+ setForwardDistance()
cl_nav2z::CbNavigateGlobal Position
+ goalPosition
+ goalYaw
+ yawTolerance
+ yawToleranceX
+ yawToleranceY
+ goalChecker_
+ CbNavigateGlobalPosition()
+ CbNavigateGlobalPosition()
+ setGoal()
+ onEntry()
+ onExit()
+ execute()
- readStartPoseFromParameter Server()
cl_nav2z::CbNavigateNext Waypoint
+ waypointsNavigator_
+ CbNavigateNextWaypoint()
+ ~CbNavigateNextWaypoint()
+ onEntry()
+ onExit()
cl_nav2z::CbRotate
+ 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()
cl_nav2z::CbNavigateBackwards
+ backwardDistance
+ backwardSpeed
+ goalChecker_
+ odomTracker_
+ CbNavigateBackwards()
+ onEntry()
+ onExit()