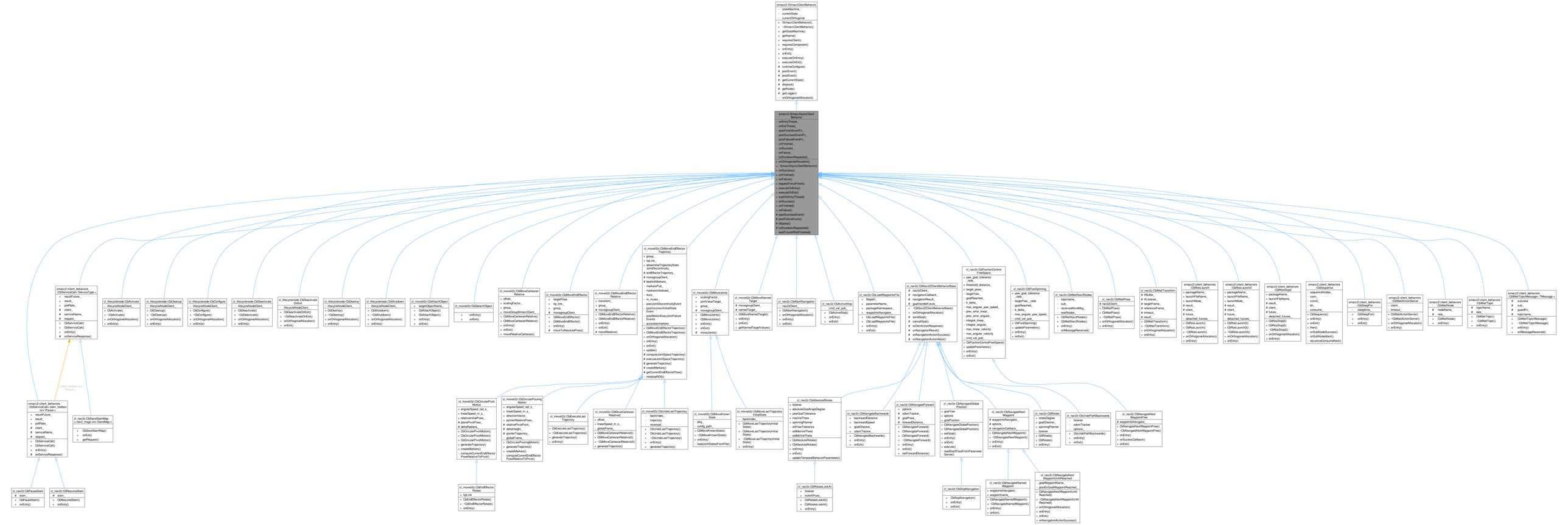
smacc2::ISmaccClientBehavior
- stateMachine_
- currentState
- currentOrthogonal
+ ISmaccClientBehavior()
+ ~ISmaccClientBehavior()
+ getStateMachine()
+ getName()
+ requireClient()
+ requireComponent()
+ onEntry()
+ onExit()
+ executeOnEntry()
+ executeOnExit()
# runtimeConfigure()
# postEvent()
# postEvent()
# getCurrentState()
# dispose()
# getNode()
# getLogger()
# initOrthogonal(Allocation)
smacc2::ISmaccAsyncClientBehavior
- onEntryThread_
- onExitThread_
- postFinishEventFn_
- postSuccessEventFn_
- postFailureEventFn_
- onFinished_
- onSuccess_
- onFailure_
- isShutdownRequested_
+ onOrthogonalAllocation()
+ ~ISmaccAsyncClientBehavior()
+ onSuccess()
+ onFinished()
+ onFailure()
+ requestForceFinish()
+ executeOnEntry()
+ executeOnExit()
+ waitOnEntryThread()
+ onSuccess()
+ onFinished()
+ onFailure()
# postSuccessEvent()
# postFailureEvent()
# dispose()
# isShutdownRequested()
# waitFutureIfNotFinished()
smacc2::client_behaviors::CbServiceCall< Service,Type >
+ resultFuture_
+ result_
+ pollRate_
# client_
# serviceName_
# request_
+ CbServiceCall()
+ CbServiceCall()
+ onEntry()
# onServiceResponse()
cl_lifecyclenode::CbActivate
- lifecycleNodeClient_
+ CbActivate()
+ ~CbActivate()
+ onOrthogonalAllocation()
+ onEntry()
cl_lifecyclenode::CbCleanup
- lifecycleNodeClient_
+ CbCleanup()
+ ~CbCleanup()
+ onOrthogonalAllocation()
+ onEntry()
cl_lifecyclenode::CbConfigure
- lifecycleNodeClient_
+ CbConfigure()
+ ~CbConfigure()
+ onOrthogonalAllocation()
+ onEntry()
cl_lifecyclenode::CbDeactivate
- lifecycleNodeClient_
+ CbDeactivate()
+ ~CbDeactivate()
+ onOrthogonalAllocation()
+ onEntry()
cl_lifecyclenode::CbDeactivateOnExit
- lifecycleNodeClient_
+ CbDeactivateOnExit()
+ ~CbDeactivateOnExit()
+ onOrthogonalAllocation()
+ onExit()
cl_lifecyclenode::CbDestroy
- lifecycleNodeClient_
+ CbDestroy()
+ ~CbDestroy()
+ onOrthogonalAllocation()
+ onEntry()
cl_lifecyclenode::CbShutdown
- lifecycleNodeClient_
+ CbShutdown()
+ ~CbShutdown()
+ onOrthogonalAllocation()
+ onEntry()
cl_movel32::CbAttachObject
+ targetObjectName_
+ CbAttachObject()
+ ~CbAttachObject()
+ onEntry()
+ onExit()
cl_movel32::CbDetachObject
+ onEntry()
+ onExit()
cl_movel32::CbMoveCartesianRelative
+ offset_
+ scalingFactor_
+ group_
+ moveGroupSmaccClient_
+ CbMoveCartesianRelative()
+ CbMoveCartesianRelative()
+ onEntry()
+ onExit()
+ moveRelativeCartesian()
cl_movel32::CbMoveEndEffectorTrajectory
+ targetPose
+ tip_link_
+ group_
# moveGroupClient_
+ CbMoveEndEffectorTrajectory()
+ CbMoveEndEffectorTrajectory()
+ onEntry()
# moveToAbsolutePose()
cl_movel32::CbMoveEndEffectorRelative
+ transform_
+ group_
# moveGroupClient_
+ CbMoveEndEffectorRelative()
+ CbMoveEndEffectorRelative()
+ onEntry()
+ onExit()
# moveRelative()
cl_movel32::CbMoveEndEffectorTrajectory
+ group_
+ tip_link_
+ allowInitialTrajectoryStateJointDiscontinuity_
# endEffectorTrajectory_
# moveGroupClient_
# beginNoMarkers_
# markersPub_
# markersInitialized_
# lkarv_
# m_mutex_
# postJointDiscontinuityEvent
# postIncorrectInitialStateEvent
# postMotionExecutionFailureEvents
+ autoclearmarkers
+ CbMoveEndEffectorTrajectory()
+ CbMoveEndEffectorTrajectory()
+ onOrthogonalAllocation()
+ onEntry()
+ onExit()
+ update()
# computeJointSpaceTrajectory()
# executeJointSpaceTrajectory()
# generateTrajectory()
# createMarkers()
# getCurrentEndEffectorPose()
+ initializeROS()
cl_movel32::CbMoveJoints
+ scalingFactor
+ jointValueTarget_
+ group_
# moveGroupClient_
+ CbMoveJoints()
+ CbMoveJoints()
+ onEntry()
+ onExit()
# moveJoints()
cl_movel32::CbMoveNamedTarget
moveGroupClient_
namedTarget_
+ CbMoveNamedTarget()
+ CbMoveNamedTarget()
+ onEntry()
+ onExit()
+ getNamedTargetValues()
cl_nav2z::CbAbortNavigation
- navClient_
+ CbAbortNavigation()
+ ~CbAbortNavigation()
+ onOrthogonalAllocation()
+ onEntry()
+ onExit()
cl_nav2z::CbActivateStop
- cmd_vel_pub_
+ CbActivateStop()
+ ~CbActivateStop()
+ onEntry()
+ onExit()
cl_nav2z::CbLoadWaypointsFile
+ filepath_
+ parameterName_
+ packageNamespace_
+ waypointsNavigator_
+ CbLoadWaypointsFile()
+ CbLoadWaypointsFile()
+ onEntry()
+ onExit()
cl_nav2z::CbNavigateGlobalPosition
+ goalYaw
+ options
+ goalPosition
+ CbNavigateGlobalPosition()
+ CbNavigateGlobalPosition()
+ setGoal()
+ onEntry()
+ onExit()
+ execute()
- readStatePoseFromParameterServer()
cl_nav2z::CbNavigateNextWaypoint
waypointsNavigator_
+ CbNavigateNextWaypointTree()
+ ~CbNavigateNextWaypointTree()
+ onEntry()
+ onSuccessCallback()
+ onExit()
cl_movel32::CbCircularPouringMotion
+ angularSpeed_rad_s_
+ linearSpeed_m_s_
+ relativeInitialPose_
+ relativeFinalPose_
# deltaRadians_
+ CbCircularPouringMotion()
+ CbCircularPouringMotion()
+ CbCircularPouringMotion()
+ generateTrajectory()
+ createMarkers()
- computeCurrentEndEffectorPoseRelativeToPivot()
cl_movel32::CbCircularPouringMotion
+ angularSpeed_rad_s_
+ linearSpeed_m_s_
+ directionVector_
+ pointerRelativePose_
+ relativePivotPoint_
+ deltaHeight_
# pointerTrajectory_
- globalFrame_
+ CbCircularPouringMotion()
+ generateTrajectory()
+ createMarkers()
- computeCurrentEndEffectorPoseRelativeToPivot()
cl_movel32::CbEndEffectorRotate
+ tip_link
+ CbEndEffectorRotate()
+ ~CbEndEffectorRotate()
+ onEntry()
cl_movel32::CbExecuteLastTrajectory
+ CbExecuteLastTrajectory()
+ ~CbExecuteLastTrajectory()
+ generateTrajectory()
+ onEntry()
cl_movel32::CbMoveCartesianRelative2
+ offset_
+ linearSpeed_m_s_
- globalFrame_
+ CbMoveCartesianRelative2()
+ CbMoveCartesianRelative2()
+ CbMoveCartesianRelative2()
+ generateTrajectory()
cl_movel32::CbUnloadLastTrajectory
- backVrele_
- trajectory
- reversed
+ CbUnloadLastTrajectory()
+ CbUnloadLastTrajectory()
+ CbUnloadLastTrajectory()
+ onEntry()
+ generateTrajectory()
cl_movel32::CbMoveKnownState
- pkg_
- config_path_
+ CbMoveKnownState()
+ ~CbMoveKnownState()
+ onEntry()
- loadJointStatesFromFile()
cl_movel32::CbMoveLastTrajectoryInitialState
- backVrele_
+ CbMoveLastTrajectoryInitialState()
+ CbMoveLastTrajectoryInitialState()
- ~CbMoveLastTrajectoryInitialState()
+ onEntry()
cl_nav2z::CbAbsoluteRotate
+ listener
+ absoluteGoalAngleDegree
+ yawGoalTolerance
+ maxVelTheta
+ spinningPlanner
- isXYarrTolerance
- distMinVelTheta
- distMinVelTheta
+ CbAbsoluteRotate()
+ CbAbsoluteRotate()
+ onEntry()
+ onExit()
- updateTemporaryBehaviorParameters()
cl_nav2z::CbRotateLookAt
- listener
- lookAtPose
+ CbRotateLookAt()
+ ~CbRotateLookAt()
+ onEntry()
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::CbNavigateGlobalPosition
- goalYaw
- options
- goalPosition
+ CbNavigateGlobalPosition()
+ CbNavigateGlobalPosition()
+ setGoal()
+ onEntry()
+ onExit()
+ execute()
- readStatePoseFromParameterServer()
cl_nav2z::CbNavigateNextWaypoint
waypointsNavigator_
options_
navigationCallback_
+ CbNavigateNextWaypoint()
+ ~CbNavigateNextWaypoint()
+ onEntry()
+ onExit()
cl_nav2z::CbRotate
+ rotateDegree
+ goalChecker_
+ spinningPlanner
- listener
+ CbRotate()
+ CbRotate()
+ onEntry()
cl_nav2z::CbUnloadPathBackwards
- listener
- odomTracker
- options_
+ CbUnloadPathBackwards()
+ onEntry()
+ onExit()
cl_nav2z::CbNavigateNextWaypoint
waypointsNavigator_
+ CbNavigateNextWaypointTree()
+ ~CbNavigateNextWaypointTree()
+ onEntry()
+ onSuccessCallback()
+ onExit()
cl_nav2z::CbPositionControlFreeSpace
+ yaw_goal_tolerance_rads_
+ threshold_distance_
+ target_pose_
- targetYaw_
- goalReached_
- k_beta_
- max_angular_yaw_speed_
- prev_error_linear_
- prev_error_angular_
- integral_linear_
- integral_angular_
- max_linear_velocity
- max_angular_velocity
- cmd_vel_pub_
+ CbPositionControlFreeSpace()
+ updateParameters()
+ onEntry()
+ onExit()
cl_nav2z::CbPureSpinning
+ yaw_goal_tolerance_rads_
- targetYaw_rads
- goalReached_
- k_beta_
- max_angular_yaw_speed_
- cmd_vel_pub_
+ CbPureSpinning()
+ updateParameters()
+ onEntry()
+ onExit()
cl_nav2z::CbWaitNavNodes
- topicname_
- sub_
- receivedAliveMsg_
- waitNodes_
+ CbWaitNavNodes()
+ CbWaitNavNodes()
+ onEntry()
+ onMessageReceived()
cl_nav2z::CbWaitPose
+ navclient_
+ CbWaitPose()
+ CbWaitPose()
+ ~CbWaitPose()
+ onOrthogonalAllocation()
+ onEntry()
cl_nav2z::CbWaitTransform
tfBuffer_
tfListener_
targetFrame_
referenceFrame_
timeout_
result_
+ CbWaitTransform()
+ ~CbWaitTransform()
+ onOrthogonalAllocation()
+ onEntry()
smacc2::client_behaviors::CbRosLaunch
+ packageName_
+ launchFileName_
+ launchMode_
# result_
# client_
# future_
- detached_futures_
+ CbRosLaunch()
+ CbRosLaunch()
+ ~CbRosLaunch()
+ onEntry()
smacc2::client_behaviors::CbRosLaunch2
+ packageName_
+ launchFileName_
+ launchMode_
# result_
# client_
# future_
- detached_futures_
+ CbRosLaunch2()
+ CbRosLaunch2()
+ ~CbRosLaunch2()
+ onOrthogonalAllocation()
+ onEntry()
smacc2::client_behaviors::CbRosStop2
+ packageName_
+ launchFileName_
# result_
# client_
# future_
- detached_futures_
+ CbRosStop2()
+ CbRosStop2()
+ ~CbRosStop2()
+ onOrthogonalAllocation()
+ onEntry()
smacc2::client_behaviors::CbSequence
+ sequenceNodes_
- conn_
- conn2_
- sb_
- connsume_
+ CbSequence()
+ onEntry()
+ onExit()
+ then()
- onSubNodeSuccess()
- recursiveConsumeNext()
smacc2::client_behaviors::CbSleepFor
- sleeptime_
+ CbSleepFor()
+ onEntry()
+ onExit()
smacc2::client_behaviors::CbWaitActionServer
- client_
- timeout_
+ CbWaitActionServer()
+ ~CbWaitActionServer()
+ onOrthogonalAllocation()
+ onEntry()
smacc2::client_behaviors::CbWaitNode
nodeName_
rate_
+ CbWaitNode()
+ ~CbWaitNode()
+ onEntry()
smacc2::client_behaviors::CbWaitTopic
topicName_
rate_
+ CbWaitTopic()
+ ~CbWaitTopic()
+ onEntry()
smacc2::client_behaviors::CbWaitTopic<Message>::TMessage >
success
sub_
guardFn_
topicname_
+ CbWaitTopic(Message)
+ ~CbWaitTopic(Message)
+ onEntry()
+ onMessageReceived()
smacc2::client_behaviors::CbSaveCalls< Srv_toolbox::Srv::Pause >
+ resultFuture_
+ result_
+ pollRate_
# client_
# serviceName_
# request_
+ CbSaveCalls()
+ CbSaveCalls()
+ onEntry()
# onServiceResponse()
smart_toolbox::srv::Pause
cl_nav2z::CbSaveSlamMap
+ nav2_msgs::srv::SaveMap >
+ CbSaveSlamMap()
+ onExit()
+ getRequest()
cl_nav2z::CbPauseSlam
slam_
+ CbPauseSlam()
+ onEntry()
cl_nav2z::CbResumeSlam
slam_
+ CbResumeSlam()
+ onEntry()