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()

cl_nitrosz::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 >
+ 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::CbDeactivate
OnExit
- lifecycleNodeClient_
+ CbDeactivateOnExit()
+ ~CbDeactivateOnExit()
+ onOrthogonalAllocation()
+ onExit()

cl_lifecyclenode::CbDestroy
- lifecycleNodeClient_
+ CbDestroy()
+ ~CbDestroy()
+ onOrthogonalAllocation()
+ onEntry()

cl_lifecyclenode::CbShutdown
- lifecycleNodeClient_
+ CbShutdown()
+ ~CbShutdown()
+ onOrthogonalAllocation()
+ onEntry()

cl_moveit2z::CbAttachObject
+ targetObjectName_
+ CbAttachObject()
+ CbAttachObject()
+ onEntry()
+ onExit()

cl_moveit2z::CbDetachObject

+ onEntry()
+ onExit()

cl_moveit2z::CbMoveCartesian
Relative
+ offset_
+ scalingFactor_
+ group_
+ moveGroupSmaccClient_
+ CbMoveCartesianRelative()
+ CbMoveCartesianRelative()
+ onEntry()
+ onExit()
+ moveRelativeCartesian()

cl_moveit2z::CbMoveEndEffector
+ targetPose
+ tip_link_
+ group_
# movegroupClient_
+ CbMoveEndEffector()
+ CbMoveEndEffector()
+ onEntry()
# moveToAbsolutePose()

cl_moveit2z::CbMoveEndEffector
Relative
+ transform_
+ group_
# movegroupClient_
+ CbMoveEndEffectorRelative()
+ CbMoveEndEffectorRelative()
+ onEntry()
+ onExit()
# moveRelative()

cl_moveit2z::CbMoveEndEffector
Trajectory
+ 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_moveit2z::CbMoveJoints
+ scalingFactor_
+ jointValueTarget_
+ group_
# movegroupClient_
+ CbMoveJoints()
+ CbMoveJoints()
+ onEntry()
+ onExit()
# moveJoints()

cl_moveit2z::CbMoveNamed
Target
movegroupClient_
namedTarget_
+ CbMoveNamedTarget()
+ onEntry()
+ onExit()
+ getNamedTargetValues()

cl_nav2z::CbAbortNavigation
- nav2zClient_
+ CbAbortNavigation()
+ onOrthogonalAllocation()
+ onEntry()
+ onExit()

cl_nav2z::CbActiveStop
- cmd_vel_pub_
+ CbActiveStop()
+ onEntry()
+ onExit()

cl_nav2z::CbLoadWaypointsFile
+ filepath_
+ parameterName_
+ packageNamespace_
+ waypointsNavigator_
+ CbLoadWaypointsFile()
+ CbLoadWaypointsFile()
+ onEntry()
+ onExit()

cl_nav2z::CbNav2ZClientBehaviorBase
nav2zClient_
navigationCallback_
navigationResult_
goalHandleFuture_
+ ~CbNav2ZClientBehaviorBase()
+ onOrthogonalAllocation()
# sendGoal()
# cancelGoal()
# isOwnActionResponse()
# onNavigationResult()
# onNavigationActionSuccess()
# onNavigationActionAbort()

cl_nav2z::CbPositionControl
FreeSpace
+ yaw_goal_tolerance
rads
+ threshold_distance_
+ target_pose_
- targetYaw_
- goalReached_
- k_betta_
- 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_betta_
- max_angular_yaw_speed_
- cmd_vel_pub_
+ CbPureSpinning()
+ updateParameters()
+ onEntry()
+ onExit()

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()

cl_nitrosz::CbAbortNavigation
- nitroszClient_
+ CbAbortNavigation()
+ onOrthogonalAllocation()
+ onEntry()
+ onExit()

cl_nitrosz::CbActiveStop
- cmd_vel_pub_
+ CbActiveStop()
+ onEntry()
+ onExit()

cl_nitrosz::CbLoadWaypointsFile
+ filepath_
+ parameterName_
+ packageNamespace_
+ waypointsNavigator_
+ CbLoadWaypointsFile()
+ CbLoadWaypointsFile()
+ onEntry()
+ onExit()

cl_nitrosz::CbNav2ZClient
BehaviorBase
nitroszClient_
navigationCallback_
navigationResult_
goalHandleFuture_
+ ~CbNav2ZClientBehaviorBase()
+ onOrthogonalAllocation()
# sendGoal()
# cancelGoal()
# isOwnActionResponse()
# onNavigationResult()
# onNavigationActionSuccess()
# onNavigationActionAbort()

cl_nitrosz::CbPositionControl
FreeSpace
+ yaw_goal_tolerance
rads
+ threshold_distance_
+ target_pose_
- targetYaw_
- goalReached_
- k_betta_
- 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_nitrosz::CbPureSpinning
+ yaw_goal_tolerance
rads
- targetYaw__rads
- goalReached_
- k_betta_
- max_angular_yaw_speed_
- cmd_vel_pub_
+ CbPureSpinning()
+ updateParameters()
+ onEntry()
+ onExit()

cl_nitrosz::CbWaitNav2Nodes
- topicname_
- sub_
- receivedAliveMsg_
- waitNodes_
+ CbWaitNav2Nodes()
+ CbWaitNav2Nodes()
+ onEntry()
- onMessageReceived()

cl_nitrosz::CbWaitPose
nitroszClient_
+ CbWaitPose()
+ CbWaitPose()
+ ~CbWaitPose()
+ onOrthogonalAllocation()
+ onEntry()

cl_nitrosz::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()
+ onOrthogonalAllocation()
+ 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_
- bh_
- consume_

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

smacc2::client_behaviors
::CbServiceCall< ServiceType >
+ resultFuture_
+ result_
+ pollRate_
# client_
# serviceName_
# request_
+ CbServiceCall()
+ CbServiceCall()
+ onEntry()
# onServiceResponse()

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()
+ onEntry()

smacc2::client_behaviors
::CbWaitTopic
topicName_
rate_
+ CbWaitTopic()
+ ~CbWaitTopic()
+ 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_nitrosz::CbPauseSlam
slam_
+ CbPauseSlam()
+ onEntry()

cl_nitrosz::CbResumeSlam
slam_
+ CbResumeSlam()
+ onEntry()

cl_moveit2z::CbCircularPivot
Motion
+ angularSpeed_rad_s_
+ linearSpeed_m_s_
+ relativeInitialPose_
# planePivotPose_
# deltaRadians_
+ CbCircularPivotMotion()
+ CbCircularPivotMotion()
+ CbCircularPivotMotion()
+ generateTrajectory()
+ createMarkers()
- computeCurrentEndEffector
PoseRelativeToPivot()

cl_moveit2z::CbCircularPouring
Motion
+ angularSpeed_rad_s_
+ linearSpeed_m_s_
+ directionVector_
+ pointerRelativePose_
# relativePivotPoint_
# deltaHeight_
# pointerTrajectory_
- globalFrame_
+ CbCircularPouringMotion()
+ generateTrajectory()
+ createMarkers()
- computeCurrentEndEffector
PoseRelativeToPivot()

cl_moveit2z::CbExecuteLast
Trajectory

+ CbExecuteLastTrajectory()
+ ~CbExecuteLastTrajectory()
+ generateTrajectory()
+ onEntry()

cl_moveit2z::CbMoveCartesian
Relative2
+ offset_
+ linearSpeed_m_s_
- globalFrame_
+ CbMoveCartesianRelative2()
+ CbMoveCartesianRelative2()
+ ~CbMoveCartesianRelative2()
+ generateTrajectory()

cl_moveit2z::CbUndoLastTrajectory
- backIndex_
- trajectory
- reversed
+ CbUndoLastTrajectory()
+ CbUndoLastTrajectory()
+ ~CbUndoLastTrajectory()
+ onEntry()
+ generateTrajectory()

cl_moveit2z::CbEndEffector
Rotate
+ tipLink
+ CbEndEffectorRotate()
+ ~CbEndEffectorRotate()
+ onEntry()

cl_moveit2z::CbMoveKnown
State
- pkg_
- config_path_
+ CbMoveKnownState()
+ ~CbMoveKnownState()
+ onEntry()
- loadJointStatesFromFile()

cl_moveit2z::CbMoveLastTrajectory
InitialState
- 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_
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()

cl_nav2z::CbNavigateNext
WaypointFree
waypointsNavigator_
+ CbNavigateNextWaypointFree()
+ ~CbNavigateNextWaypointFree()
+ onEntry()
+ onSucessCallback()
+ onExit()

cl_nitrosz::CbAbsoluteRotate
+ listener
+ absoluteGoalAngleDegree
+ yawGoalTolerance
+ maxVelTheta
+ spinningPlanner
- oldYawTolerance
- oldMaxVelTheta
- oldMinVelTheta
+ CbAbsoluteRotate()
+ CbAbsoluteRotate()
+ onEntry()
+ onExit()
- updateTemporalBehaviorParameters()

cl_nitrosz::CbNavigateBackwards
+ backwardDistance
+ backwardSpeed
+ goalChecker_
+ odomTracker_
+ CbNavigateBackwards()
+ onEntry()
+ onExit()

cl_nitrosz::CbNavigateForward
+ options
# odomTracker_
# goalPose_
# forwardDistance_
+ CbNavigateForward()
+ CbNavigateForward()
+ CbNavigateForward()
+ ~CbNavigateForward()
+ onEntry()
+ onExit()
+ setForwardDistance()

cl_nitrosz::CbNavigateGlobal
Position
+ goalYaw
+ options
+ goalPosition
+ CbNavigateGlobalPosition()
+ CbNavigateGlobalPosition()
+ setGoal()
+ onEntry()
+ onExit()
+ execute()
- readStartPoseFromParameter
Server()

cl_nitrosz::CbNavigateNext
Waypoint
waypointsNavigator_
options_
navigationCallback_
+ CbNavigateNextWaypoint()
+ ~CbNavigateNextWaypoint()
+ onEntry()
+ onExit()

cl_nitrosz::CbRotate
+ rotateDegree
+ goalChecker_
+ spinningPlanner
- listener
+ CbRotate()
+ CbRotate()
+ onEntry()

cl_nitrosz::CbUndoPathBackwards
- listener
- odomTracker
- options_
+ CbUndoPathBackwards()
+ onEntry()
+ onExit()

cl_nitrosz::CbRotateLookAt
+ listener
+ lookAtPose_
+ CbRotateLookAt()
+ CbRotateLookAt()
+ onEntry()

cl_nitrosz::CbStopNavigation

+ CbStopNavigation()
+ onEntry()
+ onExit()

cl_nitrosz::CbNavigateNamed
Waypoint
+ waypointsNavigator_
+ waypointname_
+ CbNavigateNamedWaypoint()
+ ~CbNavigateNamedWaypoint()
+ onEntry()
+ onExit()

cl_nitrosz::CbNavigateNext
WaypointUntilReached
- goalWaypointName_
- postEvGoalWaypointReached_
+ CbNavigateNextWaypointUntil
Reached()
+ ~CbNavigateNextWaypointUntil
Reached()
+ onOrthogonalAllocation()
+ onEntry()
+ onExit()
+ onNavigationActionSuccess()

cl_nitrosz::CbNavigateNext
WaypointFree
waypointsNavigator_
+ CbNavigateNextWaypointFree()
+ ~CbNavigateNextWaypointFree()
+ onEntry()
+ onSucessCallback()
+ onExit()

< slam_toolbox::srv
::Pause >

cl_nav2z::CbSaveSlamMap
< nav2_msgs::srv::SaveMap >

+ CbSaveSlamMap()
+ onExit()
+ getRequest()

cl_nitrosz::CbSaveSlamMap
< nav2_msgs::srv::SaveMap >

+ CbSaveSlamMap()
+ onExit()
+ getRequest()

cl_http::CbHttpRequestBase
- kRequestType
- cl_http_
+ CbHttpRequestBase()
+ onOrthogonalAllocation()
+ runtimeConfigure()
+ onResponseReceived()
+ onEntry()
+ onExit()

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()

smacc2::CbServiceServerCallback
Base< TService >
attachedClient_
+ onEntry()
+ onServiceRequestReceived()

smacc2::client_behaviors
::CbSubscriptionCallbackBase
< TMsg >
attachedClient_
+ onEntry()
+ onMessageReceived()

cl_http::CbHttpGetRequest

+ CbHttpGetRequest()

cl_http::CbHttpPostRequest

+ CbHttpPostRequest()