cl_nitrosz::CbUndoPathBackwards
+ CbUndoPathBackwards()
+ onEntry()
+ onExit()
-odomTracker
-listener
-options_
shared_ptr< tf2_ros ::Buffer >
optional< cl_nitrosz ::CbUndoPathBackwardsOptions >
cl_nitrosz::CbNav2ZClient BehaviorBase
+ ~CbNav2ZClientBehaviorBase()
+ onOrthogonalAllocation()
# sendGoal()
# cancelGoal()
# isOwnActionResponse()
# onNavigationResult()
# onNavigationActionSuccess()
# onNavigationActionAbort()
#navigationResult_
#goalHandleFuture_
ResultCode
shared_future< std ::shared_ptr< rclcpp _action::ClientGoalHandle < nav2_msgs::action::NavigateTo Pose > > >
cl_nitrosz::ClNitrosZ
cl_nitrosz::odom_tracker ::CpOdomTracker
+ CpOdomTracker()
+ processOdometryMessage()
+ setWorkingMode()
+ setPublishMessages()
+ pushPath()
+ pushPath()
+ popPath()
+ clearPath()
+ setStartPoint()
+ setStartPoint()
+ setCurrentMotionGoal()
+ setCurrentPathName()
+ getCurrentMotionGoal()
+ getPath()
+ logStateString()
# onInitialize()
# updateConfiguration()
# rtPublishPaths()
# updateRecordPath()
# updateClearPath()
# updateAggregatedStackPath()
#navigationCallback_
#aggregatedStackPathMsg
#baseTrajectory_
#workingMode_
#pathStack_
#pathInfos_
#currentMotionGoal_
#publishMessages
#subscribeToOdometryTopic_
-isShutdownRequested_
bool
Path
WorkingMode
vector< nav_msgs::msg ::Path >
vector< cl_nitrosz ::odom_tracker::CpOdomTracker ::PathInfo >
optional< geometry _msgs::msg::PoseStamped >
smacc2::ISmaccClientBehavior
+ ISmaccClientBehavior()
+ ~ISmaccClientBehavior()
+ getStateMachine()
+ getName()
+ requiresClient()
+ requiresComponent()
+ onEntry()
+ onExit()
+ executeOnEntry()
+ executeOnExit()
# runtimeConfigure()
# postEvent()
# postEvent()
# getCurrentState()
# dispose()
# getNode()
# getLogger()
- onOrthogonalAllocation()
-currentState
#owner_
smacc2::ISmaccComponent
+ ISmaccComponent()
+ ~ISmaccComponent()
+ getName()
# onInitialize()
# postEvent()
# postEvent()
# onOrthogonalAllocation()
# requiresComponent()
# requiresComponent()
# requiresClient()
# createSiblingComponent()
# createSiblingNamedComponent()
# getNode()
# getLogger()
# getStateMachine()
- initialize()
- setStateMachine()
smacc2::ISmaccClient
# onOrthogonalAllocation()
# createComponent()
# createNamedComponent()
# getNode()
# getLogger()
- initialize()
- setStateMachine()
- setOrthogonal()
smacc2::ISmaccStateMachine
+ ISmaccStateMachine()
+ ~ISmaccStateMachine()
+ reset()
+ stop()
+ eStop()
+ getOrthogonal()
+ getClientBehavior()
+ getOrthogonals()
+ requiresComponent()
+ postEvent()
+ postEvent()
+ getGlobalSMData()
+ setGlobalSMData()
+ mapBehavior()
+ getStateMachineName()
+ state_machine_visualization()
+ getCurrentStateInfo()
+ publishTransition()
+ onInitialize()
+ getTransitionLogHistory()
+ createSignalConnection()
+ disconnectSmaccSignalObject()
+ notifyOnStateEntryStart()
+ notifyOnStateEntryEnd()
+ notifyOnRuntimeConfigured()
+ notifyOnStateExitting()
+ notifyOnStateExited()
+ notifyOnRuntimeConfiguration Finished()
+ getCurrentStateCounter()
+ getCurrentState()
+ getStateMachineInfo()
+ buildStateMachineInfo()
+ getNode()
+ getLogger()
+ getMutex()
# checkStateMachineConsistence()
# initializeROS()
# onInitialized()
# createOrthogonal()
- lockStateMachine()
- unlockStateMachine()
- propagateEventToStateReactors()
- updateStatusMessage()
#longLivedSignalConnections_
-eventQueueMutex_
-m_mutex_
-stateMachineCurrentAction
-stateMachine_
vector< boost::signals2 ::scoped_connection >
recursive_mutex
StateMachineInternalAction
mutex
smacc2::introspection ::SmaccStateInfo
smacc2::ISmaccState
smacc2::ISmaccOrthogonal
smacc2::SignalDetector
smacc2::SmaccAsyncClient Behavior
smacc2::client_bases ::ISmaccActionClient
smacc2::client_bases ::SmaccActionClientBase < ActionType >
smacc2::client_bases ::SmaccActionClientBase < nav2_msgs::action::NavigateTo Pose >
smacc2::SmaccSignal < void()>
smacc2::SmaccSignal < void(const WrappedResult &)>