cl_nav2z::CbNavigateForward
+ CbNavigateForward()
+ CbNavigateForward()
+ CbNavigateForward()
+ ~CbNavigateForward()
+ onEntry()
+ onExit()
+ setForwardDistance()
optional< float >
#forwardDistance_
+forwardSpeed
optional< geometry _msgs::msg::Quaternion >
+forceInitialOrientation
optional< std::string >
+goalChecker_
optional< geometry _msgs::msg::PoseStamped >
#goalPose_
#odomTracker_
cl_nav2z::CbNav2ZClientBehaviorBase
+ ~CbNav2ZClientBehaviorBase()
+ onOrthogonalAllocation()
- propagateSuccessEvent()
- propagateFailureEvent()
ResultCode
#navigationResult_
#moveBaseClient_
cl_nav2z::ClNav2Z
+ ClNav2Z()
+ ~ClNav2Z()
smacc2::client_bases::SmaccActionClientBase< nav2_msgs::action::NavigateToPose >
< nav2_msgs::action::NavigateToPose >
smacc2::client_bases::SmaccActionClientBase< ActionType >
smacc2::client_bases::ISmaccActionClient
smacc2::SmaccAsyncClientBehavior
smacc2::ISmaccClientBehavior
smacc2::ISmaccClient
smacc2::ISmaccComponent
smacc2::ISmaccOrthogonal
smacc2::ISmaccStateMachine
smacc2::ISmaccState
smacc2::SignalDetector
smacc2::introspection::SmaccStateInfo
smacc2::SmaccSignal< void(const WrappedResult &)>
smacc2::SmaccSignal< void()>
smacc2::SmaccSignal< Signature, Combiner, Group, GroupCompare, SlotFunction, ExtendedSlotFunction, Mutex >
cl_nav2z::odom_tracker::OdomTracker
+ OdomTracker()
+ processOdometryMessage()
+ setWorkingMode()
+ setPublishMessages()
+ pushPath()
+ popPath()
+ clearPath()
+ setStartPoint()
+ setCurrentMotionGoal()
+ setCurrentPathName()
+ getCurrentMotionGoal()
+ getPath()
+ logStateString()
string
double
bool
mutex
Path
WorkingMode
SharedPtr
FeedbackCallback
ResultCallback
function< void(WrappedResult)>
function< void(const Feedback &)>
future< int >
function< void()>
+action_endpoint_
#name_
#currentPathName_
#odomFrame_
#odomTopicName_
#clearAngularDistanceThreshold
#clearPointDistanceThreshold
#recordAngularDistanceThreshold
#recordPointDistanceThreshold_
#currentMotionGoal_
#components_
#orthogonal_
#stateMachine_
-currentState
#owner_
+goalHandle_
+onAborted_
+onCancelled_
+onSucceeded_
+feedback_cb
-postAbortedEvent
-postCancelledEvent
-postSuccessEvent
#client_
+postFeedbackEvent
+done_cb
+lastRequest_
-onFailure_
-onFinished_
-onSuccess_
-onEntryThread_
-onExitThread_
-postFailureEventFn
-postFinishEventFn
-postSuccessEventFn
-isShutdownRequested_
#publishMessages
#subscribeToOdometryTopic_
#odomBasePathPub_
#robotBasePathStackedPub_
#odomSub_
#aggregatedStackPathMsg
#baseTrajectory_
#workingMode_
#pathStack_
#pathInfos_
#m_mutex_
#stateMachine_
#stateInfo_
#parentState_
+demangledStateName
+fullStateName
+stateMachine_
+parentState_
+depth_
+stateIndex_
+transitions_
+children_
+tid_
+staticBehaviorInfo
+stateReactorsInfo
+eventGeneratorsInfo
#currentStateInfo_
#stateMachineInfo_
#node_
#logger_
#stateReactors_
#eventGenerators_
#parentState_
#stateMachineStatusPub_
#timer_
#stateMachinePub_
#transitionLogPub_
#transitionHistoryService_
#status_msg_
#orthogonals_
-eventQueueMutex_
-m_mutex_
-stateMachineCurrentAction
-stateCallbackConnections
-globalData_
-transitionLogHistory_
-runMode_
-stateSeqCounter_
-lastState_
-end_
-initialized_
-scheduler_
-processorHandle_
-signalDetectorThread_
-updatableClients_
-updatableStateElements_
-loop_rate_hz
-statusPub_
-smaccStateMachine_
-clientBehaviors_
-signalDetector_
#clients_
-stateMachine_
-currentOrthogonal