string
SharedPtr
SmaccStatus
map< std::string, std::shared_ptr< smacc2::ISmaccOrthogonal > >
recursive_mutex
StateMachineInternalAction
list< boost::signals2::connection >
map< std::string, std::pair< std::function< std::string()>, boost::any > >
vector< smacc2_msgs::msg::SmaccTransitionLogEntry >
SMRunMode
long
shared_ptr< smacc2::introspection::SmaccStateMachineInfo >
shared_ptr< smacc2::introspection::SmaccStateInfo >
int
vector< smacc2::introspection::SmaccTransitionInfo >
vector< std::shared_ptr< smacc2::introspection::SmaccStateInfo > >
type_info *
std::enable_shared_from_this< SmaccStateInfo >
map< const std::type_info *, std::vector< smacc2::introspection::ClientBehaviorInfoEntry > >
map< const std::type_info *, std::vector< std::shared_ptr< smacc2::introspection::SmaccStateReactorInfo > > >
map< const std::type_info *, std::vector< std::shared_ptr< smacc2::introspection::SmaccEventGeneratorInfo > > >
smacc2::introspection::SmaccStateInfo
shared_ptr< rclcpp::Logger >
vector< std::shared_ptr< smacc2::StateReactor > >
vector< std::shared_ptr< smacc2::SmaccEventGenerator > >
smacc2::ISmaccState
smacc2::ISmaccStateMachine
atomic< unsigned long >
atomic< bool >
SmaccFifoScheduler *
processor_handle
thread
vector< smacc2::ISmaccUpdatable * >
double
vector< std::shared_ptr< smacc2::ISmaccClientBehavior > >
vector< std::shared_ptr< smacc2::ISmaccClient > >
smacc2::SignalDetector
smacc2::ISmaccOrthogonal
map< smacc2::ComponentKey, std::shared_ptr< smacc2::ISmaccComponent > >
smacc2::ISmaccClient
smacc2::ISmaccClientBehavior
smacc2::ISmaccComponent
boost::signals2::signal< Signature, optional_last_value< typename boost::function_traits< Signature >::result_type >, int, std::less< int >, function< Signature >, typename extended_signature< function_traits< Signature >::arity, Signature >::function_type, boost::signals2::mutex >
smacc2::SmaccSignal< Signature, Combiner, Group, GroupCompare, SlotFunction, ExtendedSlotFunction, Mutex >
boost::signals2::signal< void(const WrappedResult &), optional_last_value< typename boost::function_traits< void(const WrappedResult &) >::result_type >, int, std::less< int >, function< void(const WrappedResult &) >, typename extended_signature< function_traits< void(const WrappedResult &) >::arity, void(const WrappedResult &) >::function_type, boost::signals2::mutex >
boost::signals2::signal< void(), optional_last_value< typename boost::function_traits< void() >::result_type >, int, std::less< int >, function< void() >, typename extended_signature< function_traits< void() >::arity, void() >::function_type, boost::signals2::mutex >
smacc2::SmaccSignal< void(const WrappedResult &)>
< void(const WrappedResult &)>
smacc2::SmaccSignal< void()>
< void()>
FeedbackCallback
function< void(WrappedResult)>
function< void(const Feedback &)>
ResultCallback
optional< std::shared_future< typename GoalHandle::SharedPtr > >
smacc2::client_bases::ISmaccActionClient
smacc2::client_bases::SmaccActionClientBase< ActionType >
< nav2_msgs::action::NavigateToPose >
smacc2::client_bases::SmaccActionClientBase< nav2_msgs::action::NavigateToPose >
future< int >
function< void()>
bool
smacc2::SmaccAsyncClientBehavior
Path
WorkingMode
vector< nav_msgs::msg::Path >
vector< cl_nav2z::odom_tracker::OdomTracker::PathInfo >
mutex
cl_nav2z::odom_tracker::OdomTracker
optional< geometry_msgs::msg::PoseStamped >
cl_nav2z::ClNav2Z
ResultCode
cl_nav2z::CbNav2ZClientBehaviorBase
optional< float >
optional< geometry_msgs::msg::Quaternion >
optional< std::string >
cl_nav2z::CbNavigateForward
+action_endpoint_
#name_
+demangledStateName
+fullStateName
+stateMachine_
+parentState_
+depth_
+stateIndex_
+transitions_
+children_
+tid_
+staticBehaviorInfo
+stateReactorsInfo
+eventGeneratorsInfo
#stateInfo_
#stateMachineInfo_
#node_
#logger_
#stateReactors_
#eventGenerators_
#currentStateInfo_
#nh_
#parentState_
#currentState_
#stateMachineStatusPub_
#timer_
#stateMachinePub_
#transitionLogPub_
#transitionHistoryService_
#status_msg_
#orthogonals_
-eventQueueMutex_
-m_mutex_
-stateMachineCurrentAction
-stateCallbackConnections
-globalData_
-transitionLogHistory_
-runMode_
-stateSeqCounter_
-statusPub_
-lastState_
-end_
-initialized_
-scheduler_
-processorHandle_
-signalDetectorThread_
-updatableClients_
-updatableStateElements_
#currentPathName_
#odomFrame_
#odomTopicName_
-loop_rate_hz
-smaccStateMachine_
-clientBehaviors_
-signalDetector_
#clients_
-stateMachine_
-currentState
#components_
-orthogonal_
-currentOrthogonal
#clearAngularDistanceThreshold
#clearPointDistanceThreshold
#recordAngularDistanceThreshold
#recordPointDistanceThreshold_
#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_
#robotBasePathPub_
#robotBasePathStackedPub_
#odomSub_
#aggregatedStackPathMsg
#baseTrajectory_
#workingMode_
#pathStack_
#pathInfos_
#m_mutex_
#currentMotionGoal_
#moveBaseClient_
#navigationResult_
#odomTracker_
#goalPose_
#forwardDistance_
+forwardSpeed
+forceInitialOrientation
+goalChecker_
+ CbNavigateForward()
+ CbNavigateForward()
+ CbNavigateForward()
+ ~CbNavigateForward()
+ onEntry()
+ onExit()
+ setForwardDistance()