cl_nav2z::CbNavigateForward
+ CbNavigateForward()
+ CbNavigateForward()
+ CbNavigateForward()
+ ~CbNavigateForward()
+ onEntry()
+ onExit()
+ setForwardDistance()
optional< float >
optional< geometry _msgs::msg::Quaternion >
optional< std::string >
#forwardDistance_
+forwardSpeed
+forceInitialOrientation
+goalChecker_
#goalPose_
#odomTracker_
optional< geometry _msgs::msg::PoseStamped >
cl_nav2z::CbNav2ZClientBehaviorBase
+ ~CbNav2ZClientBehaviorBase()
+ onOrthogonalAllocation()
- propagateSuccessEvent()
- propagateFailureEvent()
#moveBaseClient_
#navigationResult_
ResultCode
cl_nav2z::ClNav2Z
+ ClNav2Z()
+ ~ClNav2Z()
smacc2::SmaccAsyncClientBehavior
smacc2::client_bases::SmaccActionClientBase< nav2_msgs::action::NavigateToPose >
< nav2_msgs::action::NavigateToPose >
smacc2::client_bases::SmaccActionClientBase< ActionType >
smacc2::client_bases::ISmaccActionClient
smacc2::SmaccSignal< void(const WrappedResult &)>
smacc2::SmaccSignal< void()>
smacc2::SmaccSignal< Signature, Combiner, Group, GroupCompare, SlotFunction, ExtendedSlotFunction, Mutex >
< void(const WrappedResult &)>
< void()>
cl_nav2z::odom_tracker::OdomTracker
+ OdomTracker()
+ processOdometryMessage()
+ setWorkingMode()
+ setPublishMessages()
+ pushPath()
+ pushPath()
+ popPath()
+ clearPath()
+ setStartPoint()
+ setStartPoint()
+ setCurrentMotionGoal()
+ setCurrentPathName()
+ getCurrentMotionGoal()
+ getPath()
+ logStateString()
# onInitialize()
# updateConfiguration()
# rtPublishPaths()
# updateRecordPath()
# updateClearPath()
# updateAggregatedStackPath()
#aggregatedStackPathMsg_
#baseTrajectory_
#workingMode_
#pathStack_
#pathInfos_
#m_mutex_
#currentMotionGoal_
# requiresComponent()
# requiresClient()
# createSiblingComponent()
# createSiblingNamedComponent()
# getNode()
# getLogger()
# getStateMachine()
- initialize()
- setStateMachine()
smacc2::ISmaccComponent
smacc2::ISmaccClient
smacc2::ISmaccClientBehavior
smacc2::ISmaccOrthogonal
smacc2::ISmaccStateMachine
smacc2::ISmaccState
smacc2::SignalDetector
smacc2::introspection::SmaccStateInfo
string
double
bool
long
SharedPtr
mutex
Path
WorkingMode
#currentPathName_
#odomFrame_
#odomTopicName_
#clearAngularDistanceThreshold_
#clearPointDistanceThreshold_
#recordAngularDistanceThreshold_
#recordPointDistanceThreshold_
#publishMessages
#subscribeToOdometryTopic_
#odomSub_
#stateMachine_
#currentState_
#stateInfo_
+action_endpoint_
+goalHandle_
+feedback_cb
+done_cb
+lastRequest_
#client_
+postFeedbackEvent
-onFailure_
-onFinished_
-onSuccess_
-isShutdownRequested_
-onEntryThread_
-onExitThread_
#orthogonal_
#components_
#owner_
-currentOrthogonal
#clients_
-clientBehaviors_
-signalDetector_
-smaccStateMachine_
-statusPub_
-loop_rate_hz
-lastState_
-end_
-initialized_
-scheduler_
-processorHandle_
-signalDetectorThread_
-updatableClients_
-updatableStateElements_
#name_
#parentState_