cl_nav2z::CbNavigateForward
+ CbNavigateForward()
+ CbNavigateForward()
+ CbNavigateForward()
+ ~CbNavigateForward()
+ onEntry()
+ onExit()
+ setForwardDistance()
#forwardDistance_
+forwardSpeed
+forceInitialOrientation
+goalChecker_
#goalPose_
#odomTracker_
optional< float >
optional< geometry _msgs::msg::Quaternion >
optional< std::string >
optional< geometry _msgs::msg::PoseStamped >
cl_nav2z::CbNav2ZClientBehaviorBase
+ ~CbNav2ZClientBehaviorBase()
+ onOrthogonalAllocation()
- propagateSuccessEvent()
- propagateFailureEvent()
#moveBaseClient_
#navigationResult_
ResultCode
cl_nav2z::ClNav2Z
+ ClNav2Z()
+ ~ClNav2Z()
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_
#odomBasePathPub_
#robotBasePathStackedPub_
#odomSub_
#publishMessages
#subscribeToOdometryTopic_
#currentPathName_
#odomFrame_
#odomTopicName_
#clearAngularDistanceThreshold
#clearPointDistanceThreshold
#recordAngularDistanceThreshold
#recordPointDistanceThreshold_
SharedPtr
Path
WorkingMode
vector< nav_msgs::msg ::Path >
vector< cl_nav2z::odom _tracker::OdomTracker ::PathInfo >
mutex
bool
double
string
smacc2::SmaccAsyncClient Behavior
smacc2::client_bases ::SmaccActionClientBase < nav2_msgs::action::NavigateTo Pose >
< 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()>
FeedbackCallback
function< void(WrappedResult)>
function< void(const Feedback &)>
ResultCallback
optional< std::shared _future< typename GoalHandle ::SharedPtr > >
future< int >
function< void()>
+action_endpoint_
#goalHandle_
+onAborted_
+onCancelled_
+onSucceeded_
+feedback_cb
+postAbortedEvent
+postCancelledEvent
+postSuccessEvent
#client_
+postFeedbackEvent
+done_cb
#lastRequest_
-onEntryThread_
-onExitThread_
-postFailureEventFn
-postFinishEventFn
-postSuccessEventFn
-isShutdownRequested_
-onFailure_
-onFinished_
-onSuccess_
smacc2::ISmaccClient
smacc2::ISmaccClientBehavior
smacc2::ISmaccComponent
smacc2::ISmaccOrthogonal
smacc2::ISmaccStateMachine
smacc2::SignalDetector
smacc2::ISmaccState
smacc2::introspection ::SmaccStateInfo
#components_
#owner_
-orthogonal_
-currentOrthogonal
-stateMachine_
#stateMachine_
#clients_
-clientBehaviors_
-signalDetector_
-smaccStateMachine_
-currentState
-statusPub_
-loop_rate_hz
-updatableClients_
-updatableStateElements_
-signalDetectorThread_
-processorHandle_
-scheduler_
-end_
-initialized_
-lastState_
#name_
atomic< unsigned long >
atomic< bool >
SmaccFifoScheduler *
processor_handle
thread
vector< smacc2::ISmaccUpdatable * >
map< smacc2::ComponentKey, std::shared_ptr< smacc2 ::ISmaccComponent > >
vector< std::shared _ptr< smacc2::ISmaccClient Behavior > >
vector< std::shared _ptr< smacc2::ISmaccClient > >
#stateMachineStatusPub_
#timer_
#stateMachinePub_
#transitionLogPub_
#transitionHistoryService_
#status_msg_
#orthogonals_
#eventQueueMutex_
-m_mutex_
#stateMachineCurrentAction
-stateCallbackConnections
-globalData_
-transitionLogHistory_
-runMode_
-stateSeqCounter_
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
#stateMachineInfo_
#currentStateInfo_
#currentState_
#parentState_
#stateInfo_
#nh_
#node_
#logger_
#stateReactors_
#eventGenerators_
shared_ptr< rclcpp ::Logger >
vector< std::shared _ptr< smacc2::StateReactor > >
vector< std::shared _ptr< smacc2::SmaccEventGenerator > >
shared_ptr< smacc2 ::introspection::SmaccState MachineInfo >
shared_ptr< smacc2 ::introspection::SmaccState Info >
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::SmaccStateReactor Info > > >
map< const std::type _info *, std::vector < std::shared_ptr< smacc2 ::introspection::SmaccEventGenerator Info > > >
+demangledStateName
+fullStateName
+stateMachine_
+parentState_
+depth_
+stateIndex_
+transitions_
+children_
+tid_
+staticBehaviorInfo
+stateReactorsInfo
+eventGeneratorsInfo
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 >
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 >