cl_nitrosz::CbNavigateBackwards
+ CbNavigateBackwards()
+ onEntry()
+ onExit()
+backwardDistance
+backwardSpeed
+goalChecker_
+odomTracker_
float
optional< float >
optional< std::string >
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::NavigateToPose > > >
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()
#aggregatedStackPathMsg_
#baseTrajectory_
#workingMode_
#pathStack_
cl_nitrosz::ClNitrosZ
+ ClNitrosZ()
+ ~ClNitrosZ()
smacc2::client_bases ::SmaccActionClientBase < ActionType >
+ SmaccActionClientBase()
+ SmaccActionClientBase()
+ ~SmaccActionClientBase()
+ getClientBase()
+ onInitialize()
+ waitForServer()
+ postResultEvent()
+ onOrthogonalAllocation()
+ onSucceeded()
+ onSucceeded()
+ onAborted()
+ onAborted()
+ onCancelled()
+ onCancelled()
+ cancelGoal()
+ sendGoal()
+ getEventLabel()
# onFeedback()
# onResult()
< nav2_msgs::action ::NavigateToPose >
smacc2::client_bases ::SmaccActionClientBase < nav2_msgs::action::NavigateToPose >
+lastRequest_
+feedback_cb
#client_
+postFeedbackEvent
+onAborted_
+onCancelled_
+onSucceeded_
smacc2::client_bases ::ISmaccActionClient
smacc2::SmaccAsyncClient Behavior
smacc2::ISmaccClientBehavior
smacc2::ISmaccComponent
smacc2::ISmaccClient
smacc2::ISmaccState
smacc2::ISmaccOrthogonal
smacc2::introspection ::SmaccStateInfo
smacc2::ISmaccStateMachine
smacc2::SignalDetector