cl_nav2z::CbNavigateForward
+ CbNavigateForward()
+ CbNavigateForward()
+ CbNavigateForward()
+ ~CbNavigateForward()
+ onEntry()
+ onExit()
+ setForwardDistance()
optional< float >
#forwardDistance_
+forwardSpeed
optional< geometry_msgs::msg::Quaternion >
+forceInitialOrientation
optional< std::string >
+goalChecker_
#odomTracker_
#goalPose_
optional< geometry_msgs::msg::PoseStamped >
#currentMotionGoal_
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_
#odomSub_
#robotBasePathPub_
#robotBasePathStackedPub_
#publishMessages
#subscribeToOdometryTopic_
#currentPathName_
#odomFrame_
#odomTopicName_
#clearAngularDistanceThreshold_
#clearPointDistanceThreshold_
#recordAngularDistanceThreshold_
#recordPointDistanceThreshold_
cl_nav2z::CbNav2ZClientBehaviorBase
+ ~CbNav2ZClientBehaviorBase()
+ onOrthogonalAllocation()
- propagateSuccessEvent()
- propagateFailureEvent()
#moveBaseClient_
#navigationResult_
ResultCode
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 >
< void(const WrappedResult &)>
< void()>
+action_endpoint_
+onAborted_
+onCancelled_
+onSucceeded_
+feedback_cb
+postAbortedEvent
+postCancelledEvent
+postSuccessEvent
#client_
+postFeedbackEvent
+done_cb
#lastRequest_
#goalHandle_
-onFailure_
-onFinished_
-onSuccess_
-onEntryThread_
-onExitThread_
-postFailureEventFn
-postFinishEventFn
-postSuccessEventFn
-isShutdownRequested_
#owner_
#stateMachine_
-currentOrthogonal
#components_
#orthogonal_
-stateMachine_
#clients_
-clientBehaviors_
-signalDetector_
-smaccStateMachine_
-currentState
#currentState_
#stateInfo_
#parentState_
-loop_rate_hz
-updatableClients_
-updatableStateElements_
-statusPub_
-signalDetectorThread_
-processorHandle_
-scheduler_
-end_
-initialized_
-lastState_
#name_
string
double
bool
long
SharedPtr
FeedbackCallback
ResultCallback
function< void(WrappedResult)>
function< void(const Feedback &)>
optional< std::shared_future< typename GoalHandle::SharedPtr > >
future< int >
function< void()>
Path
WorkingMode
vector< nav_msgs::msg::Path >
vector< cl_nav2z::odom_tracker::OdomTracker::PathInfo >
mutex
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::ISmaccClientBehavior > >
vector< std::shared_ptr< smacc2::ISmaccClient > >
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
shared_ptr< rclcpp::Logger >
vector< std::shared_ptr< smacc2::StateReactor > >
vector< std::shared_ptr< smacc2::SmaccEventGenerator > >
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 >
#stateMachineStatusPub_
#timer_
#stateMachinePub_
#transitionLogPub_
#transitionHistoryService_
#status_msg_
#orthogonals_
-eventQueueMutex_
-m_mutex_
-stateMachineCurrentAction
-stateCallbackConnections
-globalData_
-transitionLogHistory_
-runMode_
-stateSeqCounter_
#stateMachineInfo_
#nh_
#node_
#logger_
#stateReactors_
#eventGenerators_
#currentStateInfo_
+demangledStateName
+fullStateName
+stateMachine_
+parentState_
+depth_
+stateIndex_
+transitions_
+children_
+tid_
+staticBehaviorInfo
+stateReactorsInfo
+eventGeneratorsInfo