



ros::Time type



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### roscpp/Overview/Time - ROS Wiki

[wiki.ros.org/roscpp/Overview/Time](http://wiki.ros.org/roscpp/Overview/Time) ▼

Jul 10, 2017 - Time and Duration. See also: `ros::TimeBase` API docs, `ros::DurationBase` API docs. ROS has builtin time and duration primitive **types**, which roslib provides as the `ros::Time` and `ros::Duration` classes, respectively. A Time is a specific moment (e.g. "today at 5pm") whereas a Duration is a period of time (e.g. ...

[Time and Duration](#) · [Getting the Current Time](#) · [Creating Time and Duration](#) ...

### rostime: ros::Time Class Reference

[docs.ros.org/diamondback/api/rostime/html/classros\\_1\\_1Time.html](http://docs.ros.org/diamondback/api/rostime/html/classros_1_1Time.html) ▼

`ros::Time` Class Reference. Time representation. May either represent wall clock time or ROS clock time. More... #include <time.h>. Inheritance diagram for `ros::Time`: Inheritance graph ...

### msg - ROS Wiki

[wiki.ros.org/msg](http://wiki.ros.org/msg) ▼

Aug 22, 2017 - `bool` in C++ is aliased to `uint8_t` because of array **types**: `std::vector<bool>` is in fact a specialized form of vector that is not a container. ... `stamp.nsecs`: nanoseconds since `stamp_secs` # `time`-handling sugar is provided by the client library `time` `stamp` #Frame this data is associated with string `frame_id`.

[Message Description](#) ... · [Fields](#) · [Constants](#)

### rospy/Overview/Time - ROS Wiki

[wiki.ros.org/rospy/Overview/Time](http://wiki.ros.org/rospy/Overview/Time) ▼

Sep 27, 2016 - Time and Duration. ROS has builtin `time` and duration primitive **types**, which rospy provides as the `rospy.Time` and `rospy.Duration` classes, respectively. A `Time` is a specific moment (e.g. "today at 5pm") whereas a `Duration` is a period of `time` (e.g. "5 hours"). Durations can be negative. Times and durations ...

[Time and Duration](#) · [Getting the current time](#) · [Converting Time and](#) ...

### rospy.rostime.Time

[docs.ros.org/diamondback/api/rospy/html/rospy.rostime.Time-class.html](http://docs.ros.org/diamondback/api/rospy/html/rospy.rostime.Time-class.html) ▼

Package `rospy` :: Module `rostime` :: Class `Time` ... `Time` represents the ROS 'time' primitive **type**, which consists of two integers: seconds since epoch and nanoseconds since seconds. `Time` instances are mutable. ... Constructor: `secs` and `nsecs` are integers and correspond to the ROS 'time' primitive **type**. source code ...

### roscpp\_traits: ros::message\_traits::TimeStamp< M, typename boost ...

[docs.ros.org/.../roscpp.../structros\\_1\\_1message\\_\\_traits\\_1\\_1TimeStamp\\_3\\_01M\\_00\\_01t...](http://docs.ros.org/.../roscpp.../structros_1_1message__traits_1_1TimeStamp_3_01M_00_01t...)

static `ros::Time*` `ros::message_traits::TimeStamp< M, typename boost::enable_if< HasHeader< M > >::type*` `>::pointer`, (`t`, `typename boost::remove_const< M >::type &`, `m`), [`inline`, `static`] ...

### roscpp/Overview/MessagesTraits - ROS Wiki

[wiki.ros.org/roscpp/Overview/MessagesTraits](http://wiki.ros.org/roscpp/Overview/MessagesTraits) ▼

Mar 24, 2011 - Returns the frame id of the message, as pointer or value **type** as requested. Toggle line numbers 1 template<typename M> 2 struct TimeStamp 3 { 4 static `ros::Time*` `pointer(M& m)`; 5 static `ros::Time` `const*` `pointer(const M& m)`; 6 static `ros::Time` `value(const M& m)`; 7 };. Returns the timestamp of the message, ...

### tf/Overview/Data Types - ROS Wiki

[wiki.ros.org/tf/Overview/Data%20Types](http://wiki.ros.org/tf/Overview/Data%20Types) ▼

Jump to `tf::StampedTransform` - 1 /\*\* \brief The Stamped Transform datatype used by tf \*/ 2 class StampedTransform : public tf::Transform 3 { 4 public: 5 `ros::Time` `stamp_`; ///< The timestamp associated with this transform 6 `std::string` `frame_id_`; ///< The frame\_id of the coordinate frame in which this transform is defined 7 ...

### rviz/DisplayTypes/Marker - ROS Wiki

[wiki.ros.org/rviz/DisplayTypes/Marker](http://wiki.ros.org/rviz/DisplayTypes/Marker) ▼

Aug 3, 2015 - 1 visualization\_msgs::Marker `marker`; 2 `marker.header.frame_id` = "base\_link"; 3 `marker.header.stamp` = `ros::Time()`; 4 `marker.ns` = "my\_namespace"; 5 `marker.id` = 0; 6 `marker.type` = visualization\_msgs::Marker::SPHERE; 7 `marker.action` = visualization\_msgs::Marker::ADD; 8 `marker.pose.position.x` = 1; ...

### Messages - ROS Wiki

[wiki.ros.org/Messages](http://wiki.ros.org/Messages) ▼

Aug 26, 2016 - Message **types** use standard ROS naming conventions: the name of the package + / + name of the .msg file. For example, `std_msgs/msg/String.msg` ... In the case of a laser scan, for example, the stamp might correspond to the `time` at which the scan was taken. The `frame_id` field stores frame information ...

Searches related to `ros::Time` type

- ros **timestamp**
- ros time **tosec**
- ros time **python**
- ros time **to string**
- ros time **message**
- ros time **difference**
- ros **walltime**
- print ros::time**

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