

Callback-group-level Executor for ROS 2

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Other node

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Drive-Base node

onEmergencyStopMsg

onCmdVel

publishWheelTicks

reportDiagnosticsData

Other node

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Other node

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Executor

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Other node

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...

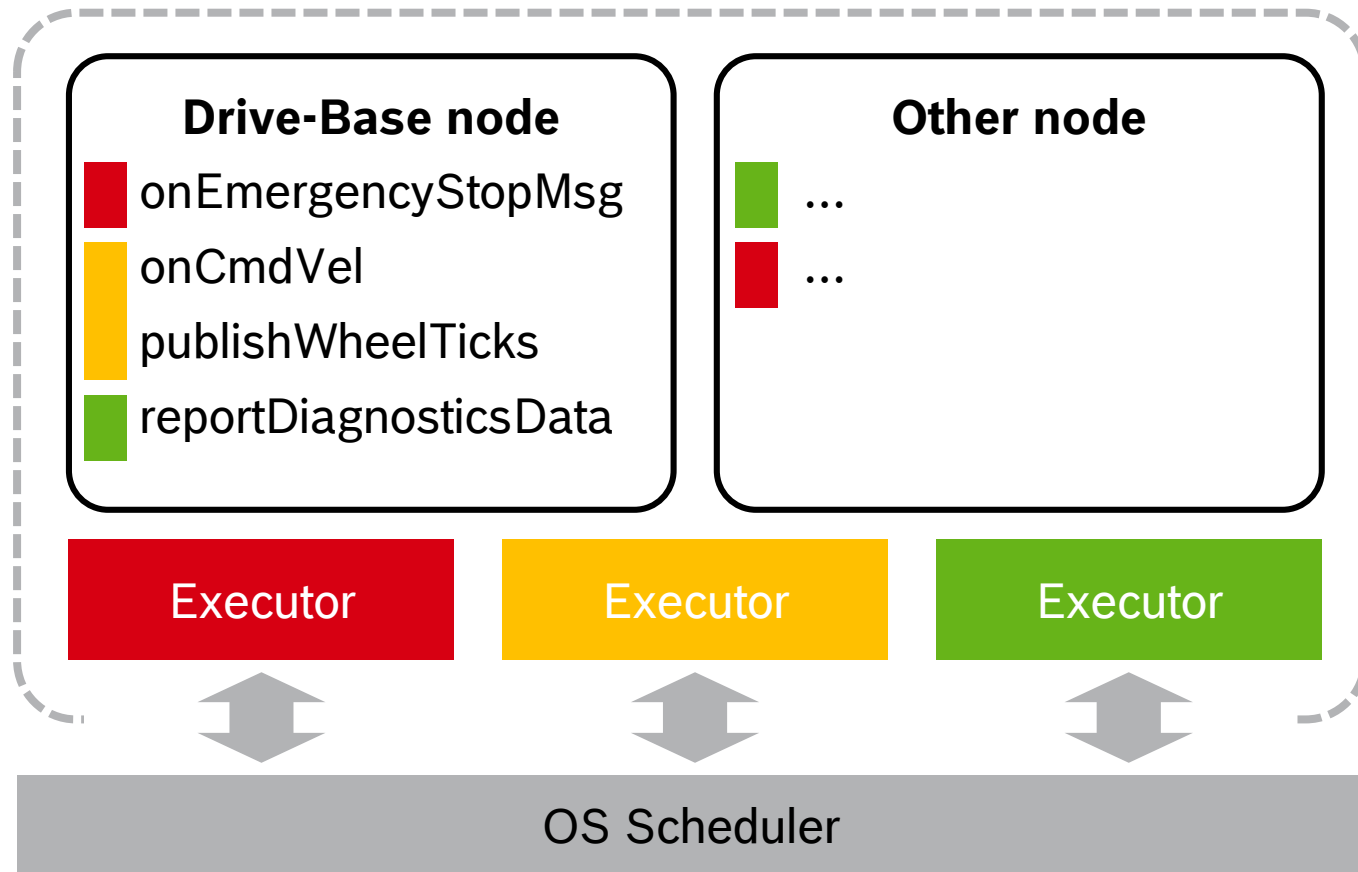
Executor

Drive-Base node

-  onEmergencyStopMsg
-  onCmdVel
- publishWheelTicks
-  reportDiagnosticsData

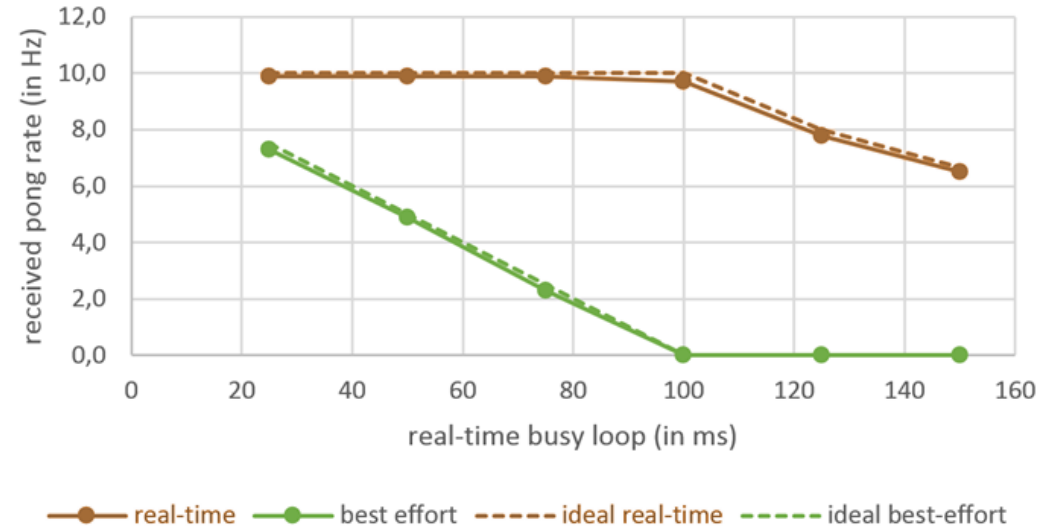
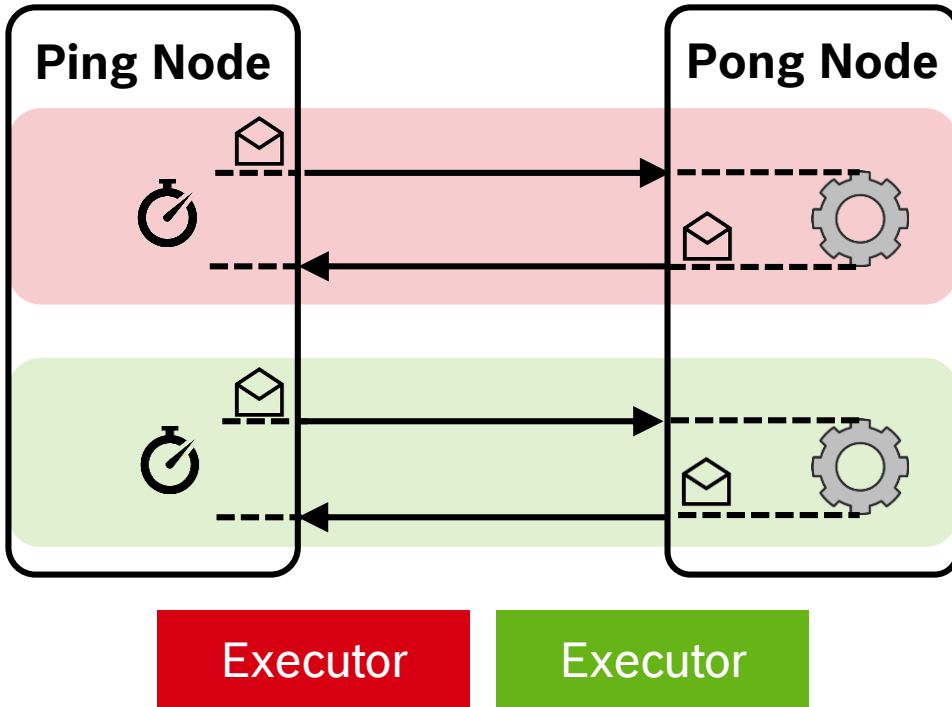
Other node

-  ...
-  ...



- Refined Executor API: nodes → callback groups
- Refined wait-sets on DDS
- Added scheduling annotations for callback-groups

github.com/boschresearch/ros2_rclcpp → meta-executor



github.com/boschresearch/ros2_examples → meta-executor

Feedback welcome!

Many thanks to William, Karsten and Dakshina!