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

...  
...
Other node

Executor

Drive-Base node
- onEmergencyStopMsg
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Executor

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!

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