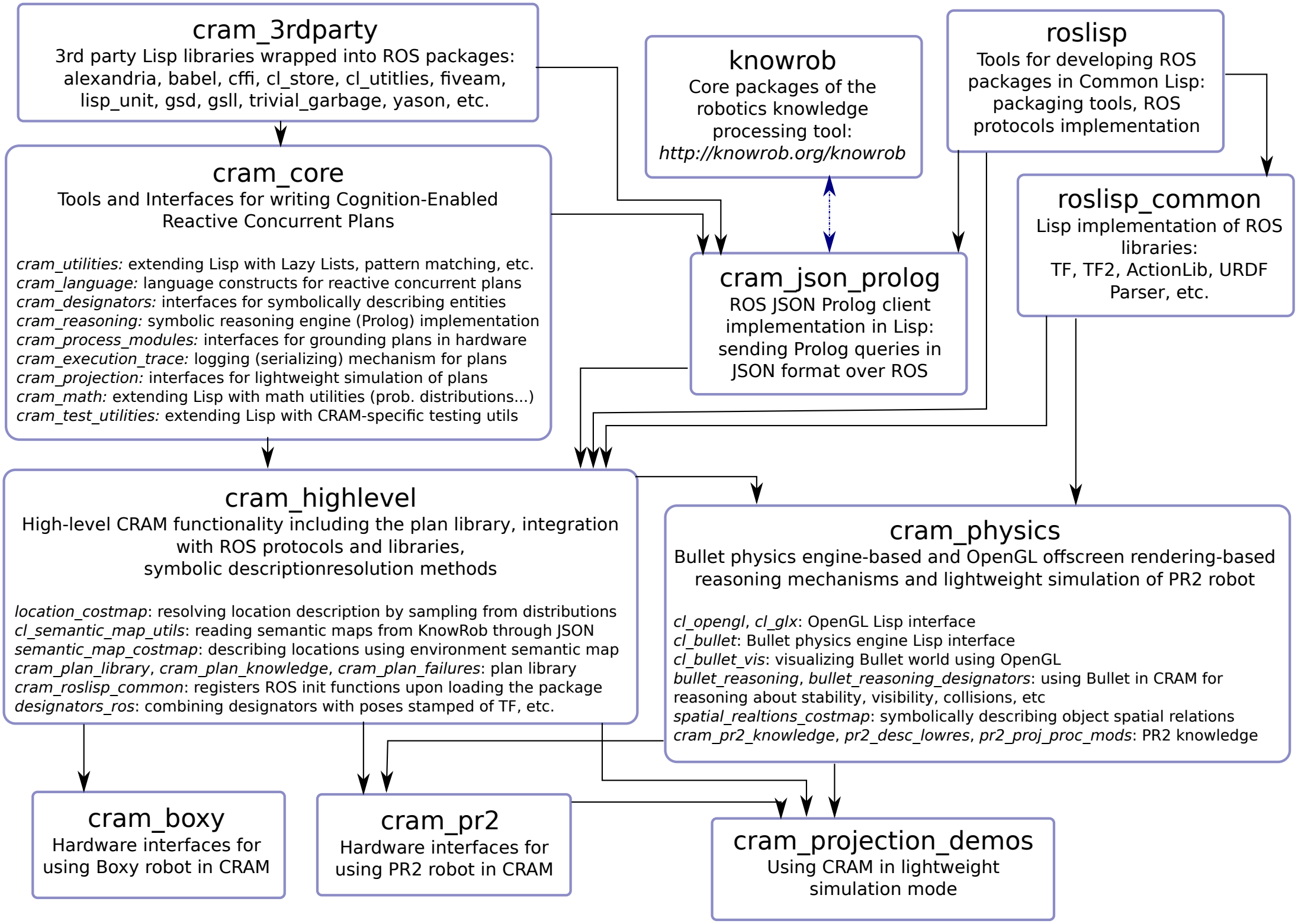
cram_3rdparty
3rd party Lisp libraries wrapped into ROS packages: alexandria, babel, cffi, cl_store, cl_utitlies, fiveam, lisp_unit, gsd, gsll, trivial_garbage, yason, etc.
knowrob
Core packages of the robotics knowledge processing tool: http://knowrob.org/knowrob
roslisp
Tools for developing ROS packages in Common Lisp: packaging tools, ROS protocols implementation
cram_core
Tools and Interfaces for writing Cognition-Enabled Reactive Concurrent Plans
cram_utilities: extending Lisp with Lazy Lists, pattern matching, etc.
cram_language: language constructs for reactive concurrent plans
cram_designators: interfaces for symbolically describing entities
cram_reasoning: symbolic reasoning engine (Prolog) implementation
cram_process_modules: interfaces for grounding plans in hardware
cram_execution_trace: logging (serializing) mechanism for plans
cram_projection: interfaces for lightweight simulation of plans
cram_math: extending Lisp with math utilities (prob. distributions...)
cram_test_utilities: extending Lisp with CRAM-specific testing utils
cram_json_prolog
ROS JSON Prolog client implementation in Lisp: sending Prolog queries in JSON format over ROS
roslisp_common
Lisp implementation of ROS libraries: TF, TF2, ActionLib, URDF Parser, etc.
cram_highlevel
High-level CRAM functionality including the plan library, integration with ROS protocols and libraries, symbolic descriptionresolution methods
location_costmap: resolving location description by sampling from distributions
cl_semantic_map_utils: reading semantic maps from KnowRob through JSON
semantic_map_costmap: describing locations using environment semantic map
cram_plan_library, cram_plan_knowledge, cram_plan_failures: plan library
cram_roslisp_common: registers ROS init functions upon loading the package
designators_ros: combining designators with poses stamped of TF, etc.
cram_physics
Bullet physics engine-based and OpenGL offscreen rendering-based reasoning mechanisms and lightweight simulation of PR2 robot
cl_opengl, cl_glx: OpenGL Lisp interface
cl_bullet: Bullet physics engine Lisp interface
cl_bullet_vis: visualizing Bullet world using OpenGL
bullet_reasoning, bullet_reasoning_designators: using Bullet in CRAM for reasoning about stability, visibility, collisions, etc
spatial_realtions_costmap: symbolically describing object spatial relations
cram_pr2_knowledge, pr2_desc_lowres, pr2_proj_proc_mods: PR2 knowledge
cram_boxy
Hardware interfaces for using Boxy robot in CRAM
cram_pr2
Hardware interfaces for using PR2 robot in CRAM
cram_projection_demos
Using CRAM in lightweight simulation mode