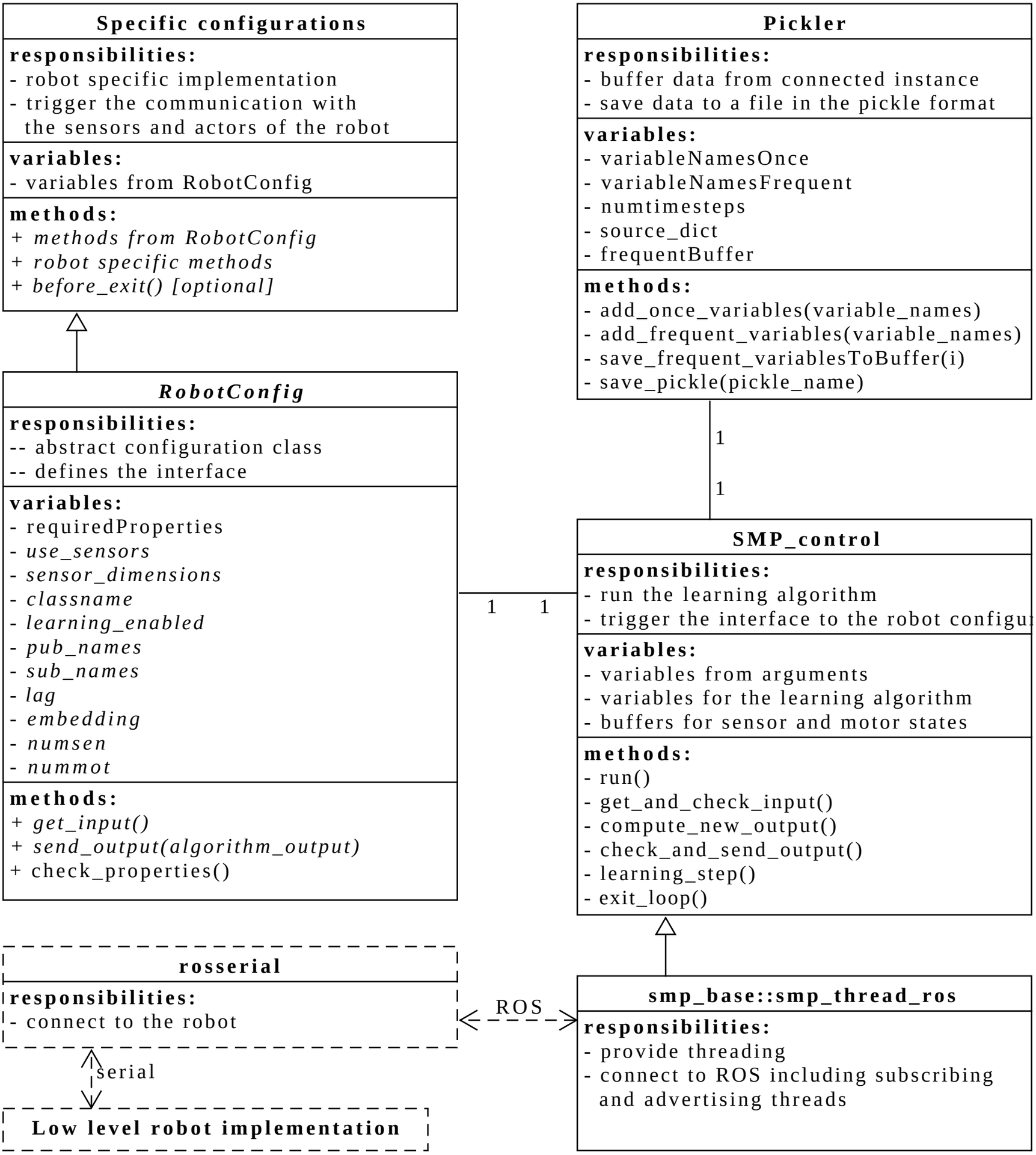
Specific configurations
responsibilities:
- robot specific implementation
- trigger the communication with the sensors and actors of the robot
variables:
- variables from RobotConfig
methods:
+ methods from RobotConfig
+ robot specific methods
+ before_exit() [optional]
Pickler
responsibilities:
- buffer data from connected instance
- save data to a file in the pickle format
variables:
- variableNamesOnce
- variableNamesFrequent
- numtimesteps
- source_dict
- frequentBuffer
methods:
- add_once_variables(variable_names)
- add_frequent_variables(variable_names)
- save_frequent_variablesToBuffer(i)
- save_pickle(pickle_name)
1
1
RobotConfig
responsibilities:
-- abstract configuration class
-- defines the interface
variables:
- requiredProperties
- use_sensors
- sensor_dimensions
- classname
- learning_enabled
- pub_names
- sub_names
- lag
- embedding
- numsen
- nummot
methods:
+ get_input()
+ send_output(algorithm_output)
+ check_properties()
1
1
SMP_control
responsibilities:
- run the learning algorithm
- trigger the interface to the robot configu
variables:
- variables from arguments
- variables for the learning algorithm
- buffers for sensor and motor states
methods:
- run()
- get_and_check_input()
- compute_new_output()
- check_and_send_output()
- learning_step()
- exit_loop()
rosserial
responsibilities:
- connect to the robot
ROS
smp_base::smp_thread_ros
responsibilities:
- provide threading
- connect to ROS including subscribing and advertising threads
serial
Low level robot implementation