

Behaviour Tree PiCar-V

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Namespace Index

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Chapter 2

Hierarchical Index

2.1 Class Hierarchy

This inheritance list is sorted roughly, but not completely, alphabetically:

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Chapter 3

Class Index

3.1 Class List

Here are the classes, structs, unions and interfaces with brief descriptions:

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behaviour_tree::CarContext	27
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Chapter 5

Namespace Documentation

5.1 `behaviour_tree` Namespace Reference

Classes

- class [BehaviourTreeHandler](#)
- class [CarContext](#)

5.2 `car` Namespace Reference

Namespaces

- namespace [configuration](#)
- namespace [plugin](#)
- namespace [system](#)

5.3 `car::configuration` Namespace Reference

Classes

- struct [Configuration](#)

5.4 `car::plugin` Namespace Reference

Classes

- class [Plugin](#)
- class [PluginManager](#)

5.5 `car::system` Namespace Reference

Namespaces

- namespace [device](#)
- namespace [logging](#)
- namespace [messaging](#)
- namespace [movement](#)

Classes

- class [CarSystem](#)

5.6 `car::system::device` Namespace Reference

Namespaces

- namespace [lidar](#)

Classes

- class [CameraDevice](#)
- class [DeviceManager](#)

5.7 `car::system::device::lidar` Namespace Reference

Classes

- class [LidarDevice](#)
- class [LidarDummy](#)
- class [LidarScanner](#)

5.8 `car::system::logging` Namespace Reference

Classes

- class [VectorSink](#)

Typedefs

- using [vector_sink_mt](#) = [VectorSink](#)< [std::mutex](#) >

5.8.1 Typedef Documentation

5.8.1.1 vector_sink_mt

```
using car::system::logging::vector_sink_mt = typedef VectorSink<std::mutex>
```

5.9 car::system::messaging Namespace Reference

Classes

- class [MessagingSystem](#)

5.10 car::system::movement Namespace Reference

Namespaces

- namespace [controller](#)

Classes

- class [MovementSystem](#)

5.11 car::system::movement::controller Namespace Reference

Classes

- class [AbstractMovementController](#)
- class [DummyMovementController](#)

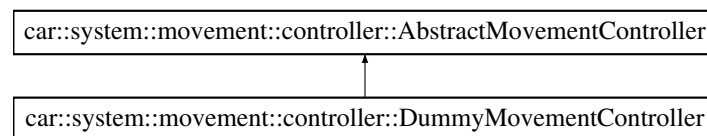
Chapter 6

Class Documentation

6.1 car::system::movement::controller::AbstractMovementController Class Reference

```
#include <AbstractMovementController.h>
```

Inheritance diagram for car::system::movement::controller::AbstractMovementController:



Public Member Functions

- virtual void [initialize](#) ()=0
- virtual void [stop](#) ()=0
- virtual void [terminate](#) ()=0
- virtual void [setRearWheelsSpeed](#) (const int speed)=0
- virtual void [setRearLeftWheelSpeed](#) (const int speed)=0
- virtual void [setRearRightWheelSpeed](#) (const int speed)=0
- virtual void [setFrontWheelsAngle](#) (const float angle)=0
- virtual void [setCameraServo1Angle](#) (const float angle)=0
- virtual void [setCameraServo2Angle](#) (const float angle)=0
- virtual void [setRearWheelsDirectionToForward](#) ()=0
- virtual void [setRearLeftWheelDirectionToForward](#) ()=0
- virtual void [setRearRightWheelDirectionToForward](#) ()=0
- virtual void [setRearWheelsDirectionToBackward](#) ()=0
- virtual void [setRearLeftWheelDirectionToBackward](#) ()=0
- virtual void [setRearRightWheelDirectionToBackward](#) ()=0

6.1.1 Member Function Documentation

6.1.1.1 initialize()

```
virtual void car::system::movement::controller::AbstractMovementController::initialize ( )  
[pure virtual]
```

Implemented in [car::system::movement::controller::DummyMovementController](#).

6.1.1.2 setCameraServo1Angle()

```
virtual void car::system::movement::controller::AbstractMovementController::setCameraServo1↵  
Angle (   
        const float angle ) [pure virtual]
```

Implemented in [car::system::movement::controller::DummyMovementController](#).

6.1.1.3 setCameraServo2Angle()

```
virtual void car::system::movement::controller::AbstractMovementController::setCameraServo2↵  
Angle (   
        const float angle ) [pure virtual]
```

Implemented in [car::system::movement::controller::DummyMovementController](#).

6.1.1.4 setFrontWheelsAngle()

```
virtual void car::system::movement::controller::AbstractMovementController::setFrontWheels↵  
Angle (   
        const float angle ) [pure virtual]
```

Implemented in [car::system::movement::controller::DummyMovementController](#).

6.1.1.5 setRearLeftWheelDirectionToBackward()

```
virtual void car::system::movement::controller::AbstractMovementController::setRearLeftWheel↵  
DirectionToBackward ( ) [pure virtual]
```

Implemented in [car::system::movement::controller::DummyMovementController](#).

6.1.1.6 setRearLeftWheelDirectionToForward()

```
virtual void car::system::movement::controller::AbstractMovementController::setRearLeftWheel↵  
DirectionToForward ( ) [pure virtual]
```

Implemented in [car::system::movement::controller::DummyMovementController](#).

6.1.1.7 setRearLeftWheelSpeed()

```
virtual void car::system::movement::controller::AbstractMovementController::setRearLeftWheel↵  
Speed (   
        const int speed ) [pure virtual]
```

Implemented in [car::system::movement::controller::DummyMovementController](#).

6.1.1.8 setRearRightWheelDirectionToBackward()

```
virtual void car::system::movement::controller::AbstractMovementController::setRearRight↵  
WheelDirectionToBackward ( ) [pure virtual]
```

Implemented in [car::system::movement::controller::DummyMovementController](#).

6.1.1.9 setRearRightWheelDirectionToForward()

```
virtual void car::system::movement::controller::AbstractMovementController::setRearRight↵  
WheelDirectionToForward ( ) [pure virtual]
```

Implemented in [car::system::movement::controller::DummyMovementController](#).

6.1.1.10 setRearRightWheelSpeed()

```
virtual void car::system::movement::controller::AbstractMovementController::setRearRight↵  
WheelSpeed (   
        const int speed ) [pure virtual]
```

Implemented in [car::system::movement::controller::DummyMovementController](#).

6.1.1.11 setRearWheelsDirectionToBackward()

```
virtual void car::system::movement::controller::AbstractMovementController::setRearWheels↵  
DirectionToBackward ( ) [pure virtual]
```

Implemented in [car::system::movement::controller::DummyMovementController](#).

6.1.1.12 setRearWheelsDirectionToForward()

```
virtual void car::system::movement::controller::AbstractMovementController::setRearWheels↵  
DirectionToForward ( ) [pure virtual]
```

Implemented in [car::system::movement::controller::DummyMovementController](#).

6.1.1.13 setRearWheelsSpeed()

```
virtual void car::system::movement::controller::AbstractMovementController::setRearWheelsSpeed  
(  
    const int speed ) [pure virtual]
```

Implemented in [car::system::movement::controller::DummyMovementController](#).

6.1.1.14 stop()

```
virtual void car::system::movement::controller::AbstractMovementController::stop ( ) [pure  
virtual]
```

Implemented in [car::system::movement::controller::DummyMovementController](#).

6.1.1.15 terminate()

```
virtual void car::system::movement::controller::AbstractMovementController::terminate ( )  
[pure virtual]
```

Implemented in [car::system::movement::controller::DummyMovementController](#).

The documentation for this class was generated from the following file:

- [include/car/system/movement/controller/AbstractMovementController.h](#)

6.2 BackWheels Class Reference

Public Member Functions

- [BackWheels](#) (const int &bus_number=1)
- void [forward](#) ()
- void [backward](#) ()
- void [stop](#) ()
- int [getSpeed](#) () const
- void [setSpeed](#) (const int &speed)
- void [ready](#) ()
- void [calibration](#) ()
- void [caliLeft](#) ()
- void [caliRight](#) ()
- void [caliOK](#) ()

Public Attributes

- PCA9685 [pca9685](#)

Private Attributes

- std::unique_ptr< TB6612 > [left_wheel](#)
- std::unique_ptr< TB6612 > [right_wheel](#)
- int [forward_A](#)
- int [forward_B](#)
- int [cali_forward_A](#)
- int [cali_forward_B](#)
- int [speed](#)

6.2.1 Constructor & Destructor Documentation

6.2.1.1 BackWheels()

```
BackWheels::BackWheels (  
    const int & bus_number = 1 ) [inline]
```

6.2.2 Member Function Documentation

6.2.2.1 backward()

```
void BackWheels::backward ( ) [inline]
```

6.2.2.2 calibration()

```
void BackWheels::calibration ( ) [inline]
```

6.2.2.3 caliLeft()

```
void BackWheels::caliLeft ( ) [inline]
```

6.2.2.4 caliOK()

```
void BackWheels::caliOK ( ) [inline]
```

6.2.2.5 caliRight()

```
void BackWheels::caliRight ( ) [inline]
```

6.2.2.6 forward()

```
void BackWheels::forward ( ) [inline]
```

6.2.2.7 getSpeed()

```
int BackWheels::getSpeed ( ) const [inline]
```

6.2.2.8 ready()

```
void BackWheels::ready ( ) [inline]
```

6.2.2.9 setSpeed()

```
void BackWheels::setSpeed (
    const int & speed ) [inline]
```

6.2.2.10 stop()

```
void BackWheels::stop ( ) [inline]
```

6.2.3 Member Data Documentation

6.2.3.1 cali_forward_A

```
int BackWheels::cali_forward_A [private]
```

6.2.3.2 cali_forward_B

```
int BackWheels::cali_forward_B [private]
```

6.2.3.3 forward_A

```
int BackWheels::forward_A [private]
```

6.2.3.4 forward_B

```
int BackWheels::forward_B [private]
```

6.2.3.5 left_wheel

```
std::unique_ptr<TB6612> BackWheels::left_wheel [private]
```

6.2.3.6 pca9685

```
PCA9685 BackWheels::pca9685
```

6.2.3.7 right_wheel

```
std::unique_ptr<TB6612> BackWheels::right_wheel [private]
```

6.2.3.8 speed

```
int BackWheels::speed [private]
```

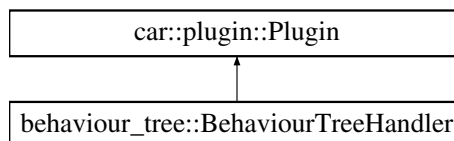
The documentation for this class was generated from the following file:

- tests/tb6612/test_rear_wheels.cpp

6.3 behaviour_tree::BehaviourTreeHandler Class Reference

```
#include <BehaviourTreeHandler.hpp>
```

Inheritance diagram for behaviour_tree::BehaviourTreeHandler:



Public Member Functions

- void [initialize](#) (std::shared_ptr< [car::system::CarSystem](#) > [car_system](#)) final override
- void [handleCommand](#) (const std::string message, const rapidjson::Document &message_json)
- void [setBehaviourTree](#) (const rapidjson::Document &message_json)
- void [startBehaviourTree](#) ()
- void [stopBehaviourTree](#) ()
- void [update](#) () final override
- void [stop](#) () final override
- std::string [getName](#) () final override
- void [_setBehaviourTree](#) (std::shared_ptr< BehaviourTree > [behaviour_tree](#))

Private Attributes

- std::shared_ptr< [car::system::CarSystem](#) > [car_system](#)
- std::shared_ptr< BehaviourTree > [behaviour_tree](#)
- std::shared_ptr< Context > [context](#)
- int [tick_count](#) = 0
- std::chrono::time_point< std::chrono::steady_clock > [last_connected](#)

6.3.1 Member Function Documentation

6.3.1.1 _setBehaviourTree()

```
void behaviour_tree::BehaviourTreeHandler::_setBehaviourTree (
    std::shared_ptr< BehaviourTree > behaviour_tree ) [inline]
```

6.3.1.2 getName()

```
std::string behaviour_tree::BehaviourTreeHandler::getName ( ) [inline], [final], [override],
[virtual]
```

Implements [car::plugin::Plugin](#).

6.3.1.3 handleCommand()

```
void behaviour_tree::BehaviourTreeHandler::handleCommand (
    const std::string message,
    const rapidjson::Document & message_json ) [inline]
```

6.3.1.4 initialize()

```
void behaviour_tree::BehaviourTreeHandler::initialize (
    std::shared_ptr< car::system::CarSystem > car_system ) [inline], [final], [override],
[virtual]
```

Implements [car::plugin::Plugin](#).

6.3.1.5 setBehaviourTree()

```
void behaviour_tree::BehaviourTreeHandler::setBehaviourTree (
    const rapidjson::Document & message_json ) [inline]
```

6.3.1.6 startBehaviourTree()

```
void behaviour_tree::BehaviourTreeHandler::startBehaviourTree ( ) [inline]
```

6.3.1.7 stop()

```
void behaviour_tree::BehaviourTreeHandler::stop ( ) [inline], [final], [override], [virtual]
```

Implements [car::plugin::Plugin](#).

6.3.1.8 stopBehaviourTree()

```
void behaviour_tree::BehaviourTreeHandler::stopBehaviourTree ( ) [inline]
```

6.3.1.9 update()

```
void behaviour_tree::BehaviourTreeHandler::update ( ) [inline], [final], [override], [virtual]
```

Implements [car::plugin::Plugin](#).

6.3.2 Member Data Documentation

6.3.2.1 behaviour_tree

```
std::shared_ptr<BehaviourTree> behaviour_tree::BehaviourTreeHandler::behaviour_tree [private]
```

6.3.2.2 car_system

```
std::shared_ptr<car::system::CarSystem> behaviour_tree::BehaviourTreeHandler::car_system  
[private]
```

6.3.2.3 context

```
std::shared_ptr<Context> behaviour_tree::BehaviourTreeHandler::context [private]
```

6.3.2.4 last_connected

```
std::chrono::time_point<std::chrono::steady_clock> behaviour_tree::BehaviourTreeHandler↵
::last_connected [private]
```

6.3.2.5 tick_count

```
int behaviour_tree::BehaviourTreeHandler::tick_count = 0 [private]
```

The documentation for this class was generated from the following file:

- include/behaviour_tree/[BehaviourTreeHandler.hpp](#)

6.4 car::system::device::CameraDevice Class Reference

```
#include <CameraDevice.h>
```

Public Member Functions

- [CameraDevice](#) (std::shared_ptr< [configuration::Configuration](#) > [configuration](#))
- [CameraDevice](#) (const [CameraDevice](#) &)=delete
- [CameraDevice](#) & operator= (const [CameraDevice](#) &)=delete
- [CameraDevice](#) ([CameraDevice](#) &&)=delete
- [CameraDevice](#) & operator= ([CameraDevice](#) &&)=delete
- [~CameraDevice](#) ()=default
- std::string [getFrameBuffer](#) () const

Static Public Member Functions

- static tl::expected< std::unique_ptr< [CameraDevice](#) >, std::string > [create](#) (std::shared_ptr< [configuration::Configuration](#) > [configuration](#))

Protected Member Functions

- void [start](#) ()
- void [update](#) ()
- void [stop](#) ()
- void [disconnect](#) ()
- void [terminate](#) ()

Private Attributes

- `std::shared_ptr< configuration::Configuration > configuration`
- `std::unique_ptr< cv::VideoCapture > camera_`
- `bool connected_ = false`
- `std::string frame_buffer_`
- `std::mutex camera_mutex_`
- `std::chrono::steady_clock::time_point last`

Friends

- class [DeviceManager](#)

6.4.1 Constructor & Destructor Documentation

6.4.1.1 CameraDevice() [1/3]

```
car::system::device::CameraDevice::CameraDevice (
    std::shared_ptr< configuration::Configuration > configuration ) [inline]
```

6.4.1.2 CameraDevice() [2/3]

```
car::system::device::CameraDevice::CameraDevice (
    const CameraDevice & ) [delete]
```

6.4.1.3 CameraDevice() [3/3]

```
car::system::device::CameraDevice::CameraDevice (
    CameraDevice && ) [delete]
```

6.4.1.4 ~CameraDevice()

```
car::system::device::CameraDevice::~~CameraDevice ( ) [default]
```

6.4.2 Member Function Documentation

6.4.2.1 create()

```
tl::expected< std::unique_ptr< CameraDevice >, std::string > car::system::device::CameraDevice::create (
    std::shared_ptr< configuration::Configuration > configuration ) [static]
```

6.4.2.2 disconnect()

```
void car::system::device::CameraDevice::disconnect ( ) [protected]
```

6.4.2.3 getFrameBuffer()

```
std::string car::system::device::CameraDevice::getFrameBuffer ( ) const
```

6.4.2.4 operator=() [1/2]

```
CameraDevice & car::system::device::CameraDevice::operator= (
    CameraDevice && ) [delete]
```

6.4.2.5 operator=() [2/2]

```
CameraDevice & car::system::device::CameraDevice::operator= (
    const CameraDevice & ) [delete]
```

6.4.2.6 start()

```
void car::system::device::CameraDevice::start ( ) [protected]
```

6.4.2.7 stop()

```
void car::system::device::CameraDevice::stop ( ) [protected]
```

6.4.2.8 terminate()

```
void car::system::device::CameraDevice::terminate ( ) [protected]
```

6.4.2.9 update()

```
void car::system::device::CameraDevice::update ( ) [protected]
```

6.4.3 Friends And Related Function Documentation

6.4.3.1 DeviceManager

```
friend class DeviceManager [friend]
```

6.4.4 Member Data Documentation

6.4.4.1 camera_

```
std::unique_ptr<cv::VideoCapture> car::system::device::CameraDevice::camera_ [private]
```

6.4.4.2 camera_mutex_

```
std::mutex car::system::device::CameraDevice::camera_mutex_ [private]
```

6.4.4.3 configuration

```
std::shared_ptr<configuration::Configuration> car::system::device::CameraDevice::configuration  
[private]
```

6.4.4.4 connected_

```
bool car::system::device::CameraDevice::connected_ = false [private]
```

6.4.4.5 frame_buffer_

```
std::string car::system::device::CameraDevice::frame_buffer_ [private]
```

6.4.4.6 last

```
std::chrono::steady_clock::time_point car::system::device::CameraDevice::last [private]
```

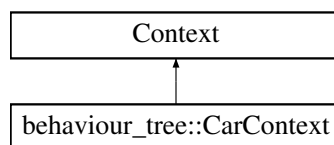
The documentation for this class was generated from the following files:

- include/car/system/device/[CameraDevice.h](#)
- src/car/system/device/[CameraDevice.cpp](#)

6.5 behaviour_tree::CarContext Class Reference

```
#include <CarContext.hpp>
```

Inheritance diagram for behaviour_tree::CarContext:



Public Member Functions

- [CarContext](#) (std::shared_ptr< BehaviourTree > behaviour_tree, std::shared_ptr< [car::system::CarSystem](#) > [car_system](#))
- std::shared_ptr< [car::system::CarSystem](#) > [getCarSystem](#) () const
- void [_](#) () override

Private Attributes

- std::shared_ptr< [car::system::CarSystem](#) > [car_system](#)

6.5.1 Constructor & Destructor Documentation

6.5.1.1 CarContext()

```
behaviour_tree::CarContext::CarContext (
    std::shared_ptr< BehaviourTree > behaviour_tree,
    std::shared_ptr< car::system::CarSystem > car_system ) [inline]
```

6.5.2 Member Function Documentation

6.5.2.1 _()

```
void behaviour_tree::CarContext::_ ( ) [inline], [override]
```

6.5.2.2 getCarSystem()

```
std::shared_ptr< car::system::CarSystem > behaviour_tree::CarContext::getCarSystem ( ) const
[inline]
```

6.5.3 Member Data Documentation

6.5.3.1 car_system

```
std::shared_ptr<car::system::CarSystem> behaviour_tree::CarContext::car_system [private]
```

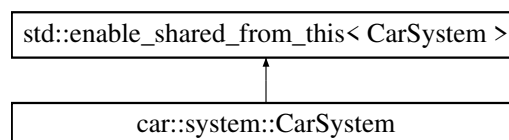
The documentation for this class was generated from the following file:

- include/behaviour_tree/[CarContext.hpp](#)

6.6 car::system::CarSystem Class Reference

```
#include <CarSystem.h>
```

Inheritance diagram for car::system::CarSystem:



Public Member Functions

- [CarSystem](#) (std::shared_ptr< [Configuration](#) > configuration, std::unique_ptr< [DeviceManager](#) > device_manager, std::unique_ptr< [MessagingSystem](#) > messaging_system, std::unique_ptr< [MovementSystem](#) > movement_system, std::unique_ptr< [PluginManager](#) > plugin_manager)
 - void [initialize](#) ()
 - void [reload](#) ()
 - void [start](#) ()
 - void [stop](#) ()
 - tl::expected< nullptr_t, std::string > [tryConnect](#) ()
 - void [disconnect](#) ()
 - void [terminate](#) ()
- Only devices should be terminated here since destructor does not work when the program is terminated by the user.*
- void [update](#) ()
 - const std::shared_ptr< [Configuration](#) > [getConfiguration](#) () const
 - void [setConfiguration](#) (std::shared_ptr< [Configuration](#) > configuration)
 - [DeviceManager](#) * [getDeviceManager](#) () const
 - [MessagingSystem](#) * [getMessagingSystem](#) () const
 - [MovementSystem](#) * [getMovementSystem](#) () const
 - template<typename T >
const std::shared_ptr< T > [getPlugin](#) () const

Private Member Functions

- void [sendData](#) ()

Private Attributes

- std::shared_ptr< [Configuration](#) > [configuration_](#)
- const std::unique_ptr< [DeviceManager](#) > [device_manager_](#)
- const std::unique_ptr< [MessagingSystem](#) > [messaging_system_](#)
- const std::unique_ptr< [MovementSystem](#) > [movement_system_](#)
- const std::unique_ptr< [PluginManager](#) > [plugin_manager_](#)
- bool [initialized](#) = false
- bool [started](#) = false

6.6.1 Constructor & Destructor Documentation

6.6.1.1 CarSystem()

```
car::system::CarSystem::CarSystem (
    std::shared_ptr< Configuration > configuration,
    std::unique_ptr< DeviceManager > device_manager,
    std::unique_ptr< MessagingSystem > messaging_system,
    std::unique_ptr< MovementSystem > movement_system,
    std::unique_ptr< PluginManager > plugin_manager )
```

6.6.2 Member Function Documentation

6.6.2.1 disconnect()

```
void car::system::CarSystem::disconnect ( )
```

6.6.2.2 getConfiguration()

```
const std::shared_ptr< Configuration > car::system::CarSystem::getConfiguration ( ) const  
[inline]
```

6.6.2.3 getDeviceManager()

```
DeviceManager * car::system::CarSystem::getDeviceManager ( ) const [inline]
```

6.6.2.4 getMessagingSystem()

```
MessagingSystem * car::system::CarSystem::getMessagingSystem ( ) const [inline]
```

6.6.2.5 getMovementSystem()

```
MovementSystem * car::system::CarSystem::getMovementSystem ( ) const [inline]
```

6.6.2.6 getPlugin()

```
template<typename T >  
const std::shared_ptr< T > car::system::CarSystem::getPlugin ( ) const [inline]
```

6.6.2.7 initialize()

```
void car::system::CarSystem::initialize ( )
```

6.6.2.8 reload()

```
void car::system::CarSystem::reload ( )
```

6.6.2.9 sendData()

```
void car::system::CarSystem::sendData ( ) [private]
```

6.6.2.10 setConfiguration()

```
void car::system::CarSystem::setConfiguration (
    std::shared_ptr< Configuration > configuration )
```

6.6.2.11 start()

```
void car::system::CarSystem::start ( )
```

6.6.2.12 stop()

```
void car::system::CarSystem::stop ( )
```

6.6.2.13 terminate()

```
void car::system::CarSystem::terminate ( )
```

Only devices should be terminated here since destructor does not work when the program is terminated by the user.

6.6.2.14 tryConnect()

```
tl::expected< nullptr_t, std::string > car::system::CarSystem::tryConnect ( )
```

6.6.2.15 update()

```
void car::system::CarSystem::update ( )
```

6.6.3 Member Data Documentation

6.6.3.1 configuration_

```
std::shared_ptr<Configuration> car::system::CarSystem::configuration_ [private]
```

6.6.3.2 device_manager_

```
const std::unique_ptr<DeviceManager> car::system::CarSystem::device_manager_ [private]
```

6.6.3.3 initialized

```
bool car::system::CarSystem::initialized = false [private]
```

6.6.3.4 messaging_system_

```
const std::unique_ptr<MessagingSystem> car::system::CarSystem::messaging_system_ [private]
```

6.6.3.5 movement_system_

```
const std::unique_ptr<MovementSystem> car::system::CarSystem::movement_system_ [private]
```

6.6.3.6 plugin_manager_

```
const std::unique_ptr<PluginManager> car::system::CarSystem::plugin_manager_ [private]
```

6.6.3.7 started

```
bool car::system::CarSystem::started = false [private]
```

The documentation for this class was generated from the following files:

- include/car/system/[CarSystem.h](#)
- src/car/system/[CarSystem.cpp](#)

6.7 car::configuration::Configuration Struct Reference

```
#include <Configuration.h>
```

Public Member Functions

- void [setCameraFps](#) (const int [camera_fps](#))
- const int [getCameraFpsInterval](#) ()

Public Attributes

- std::string [host](#) = "127.0.0.1:3000"
- int [camera_index](#) = 0
- bool [use_camera](#) = true
- std::string [lidar_port](#) = ""
- bool [use_lidar](#) = true
- std::chrono::milliseconds [behaviour_tree_update_ms_interval](#) = std::chrono::milliseconds(100)

Private Attributes

- int [camera_fps](#) = 60
- int [camera_fps_interval](#) = 1000

6.7.1 Member Function Documentation

6.7.1.1 getCameraFpsInterval()

```
const int car::configuration::Configuration::getCameraFpsInterval ( ) [inline]
```

6.7.1.2 setCameraFps()

```
void car::configuration::Configuration::setCameraFps (
    const int camera\_fps ) [inline]
```

6.7.2 Member Data Documentation

6.7.2.1 behaviour_tree_update_ms_interval

```
std::chrono::milliseconds car::configuration::Configuration::behaviour_tree_update_ms_interval  
= std::chrono::milliseconds(100)
```

6.7.2.2 camera_fps

```
int car::configuration::Configuration::camera_fps = 60 [private]
```

6.7.2.3 camera_fps_interval

```
int car::configuration::Configuration::camera_fps_interval = 1000 [private]
```

6.7.2.4 camera_index

```
int car::configuration::Configuration::camera_index = 0
```

6.7.2.5 host

```
std::string car::configuration::Configuration::host = "127.0.0.1:3000"
```

6.7.2.6 lidar_port

```
std::string car::configuration::Configuration::lidar_port = ""
```

6.7.2.7 use_camera

```
bool car::configuration::Configuration::use_camera = true
```

6.7.2.8 use_lidar

```
bool car::configuration::Configuration::use_lidar = true
```

The documentation for this struct was generated from the following file:

- include/car/configuration/[Configuration.h](#)

6.8 car::system::device::DeviceManager Class Reference

```
#include <DeviceManager.h>
```

Public Member Functions

- [DeviceManager](#) (std::unique_ptr< [CameraDevice](#) > camera_device, std::unique_ptr< [lidar::LidarDevice](#) > lidar_device)
- [CameraDevice](#) * [getCameraDevice](#) ()
- [lidar::LidarDevice](#) * [getLidarDevice](#) ()
- const bool [isRunning](#) () const
- void [initialize](#) (std::shared_ptr< [system::CarSystem](#) > car_system)
- void [start](#) ()
- void [update](#) ()
- void [stop](#) ()
- void [terminate](#) ()

Static Public Member Functions

- static tl::expected< std::unique_ptr< [DeviceManager](#) >, std::string > [create](#) (std::shared_ptr< [Configuration](#) > configuration)

Private Attributes

- std::shared_ptr< [car::system::CarSystem](#) > car_system
- bool [is_initialized_](#) = false
- bool [is_running_](#) = false
- std::unique_ptr< [lidar::LidarDevice](#) > lidar_device_
- std::unique_ptr< [CameraDevice](#) > camera_device_

6.8.1 Constructor & Destructor Documentation

6.8.1.1 DeviceManager()

```
car::system::device::DeviceManager::DeviceManager (
    std::unique_ptr< CameraDevice > camera_device,
    std::unique_ptr< lidar::LidarDevice > lidar_device ) [inline]
```

6.8.2 Member Function Documentation

6.8.2.1 create()

```
tl::expected< std::unique_ptr< DeviceManager >, std::string > car::system::device::DeviceManager::create (
    std::shared_ptr< Configuration > configuration ) [static]
```

6.8.2.2 getCameraDevice()

```
CameraDevice * car::system::device::DeviceManager::getCameraDevice ( ) [inline]
```

6.8.2.3 getLidarDevice()

```
lidar::LidarDevice * car::system::device::DeviceManager::getLidarDevice ( ) [inline]
```

6.8.2.4 initialize()

```
void car::system::device::DeviceManager::initialize (
    std::shared_ptr< system::CarSystem > car_system )
```

6.8.2.5 isRunning()

```
const bool car::system::device::DeviceManager::isRunning ( ) const [inline]
```

6.8.2.6 start()

```
void car::system::device::DeviceManager::start ( )
```


6.8.2.7 stop()

```
void car::system::device::DeviceManager::stop ( )
```

6.8.2.8 terminate()

```
void car::system::device::DeviceManager::terminate ( )
```

6.8.2.9 update()

```
void car::system::device::DeviceManager::update ( )
```

6.8.3 Member Data Documentation

6.8.3.1 camera_device_

```
std::unique_ptr<CameraDevice> car::system::device::DeviceManager::camera_device_ [private]
```

6.8.3.2 car_system

```
std::shared_ptr<car::system::CarSystem> car::system::device::DeviceManager::car_system [private]
```

6.8.3.3 is_initialized_

```
bool car::system::device::DeviceManager::is_initialized_ = false [private]
```

6.8.3.4 is_running_

```
bool car::system::device::DeviceManager::is_running_ = false [private]
```

6.8.3.5 lidar_device_

```
std::unique_ptr<lidar::LidarDevice> car::system::device::DeviceManager::lidar_device_ [private]
```

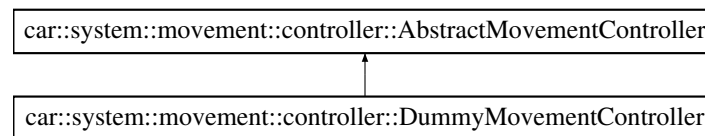
The documentation for this class was generated from the following files:

- include/car/system/device/[DeviceManager.h](#)
- src/car/system/device/[DeviceManager.cpp](#)

6.9 car::system::movement::controller::DummyMovementController Class Reference

```
#include <DummyMovementController.h>
```

Inheritance diagram for car::system::movement::controller::DummyMovementController:



Public Member Functions

- void [initialize](#) () final override
- void [stop](#) () final override
- void [terminate](#) () final override
- void [setRearWheelsSpeed](#) (const int speed) final override
- void [setRearLeftWheelSpeed](#) (const int speed) final override
- void [setRearRightWheelSpeed](#) (const int speed) final override
- void [setFrontWheelsAngle](#) (const float angle) final override
- void [setCameraServo1Angle](#) (const float angle) final override
- void [setCameraServo2Angle](#) (const float angle) final override
- void [setRearWheelsDirectionToForward](#) () final override
- void [setRearLeftWheelDirectionToForward](#) () final override
- void [setRearRightWheelDirectionToForward](#) () final override
- void [setRearWheelsDirectionToBackward](#) () final override
- void [setRearLeftWheelDirectionToBackward](#) () final override
- void [setRearRightWheelDirectionToBackward](#) () final override

6.9.1 Member Function Documentation

6.9.1.1 initialize()

```
void car::system::movement::controller::DummyMovementController::initialize ( ) [inline],  
[final], [override], [virtual]
```

Implements [car::system::movement::controller::AbstractMovementController](#).

6.9.1.2 setCameraServo1Angle()

```
void car::system::movement::controller::DummyMovementController::setCameraServo1Angle (   
    const float angle ) [final], [override], [virtual]
```

Implements [car::system::movement::controller::AbstractMovementController](#).

6.9.1.3 setCameraServo2Angle()

```
void car::system::movement::controller::DummyMovementController::setCameraServo2Angle (   
    const float angle ) [final], [override], [virtual]
```

Implements [car::system::movement::controller::AbstractMovementController](#).

6.9.1.4 setFrontWheelsAngle()

```
void car::system::movement::controller::DummyMovementController::setFrontWheelsAngle (   
    const float angle ) [final], [override], [virtual]
```

Implements [car::system::movement::controller::AbstractMovementController](#).

6.9.1.5 setRearLeftWheelDirectionToBackward()

```
void car::system::movement::controller::DummyMovementController::setRearLeftWheelDirectionTo←  
Backward ( ) [final], [override], [virtual]
```

Implements [car::system::movement::controller::AbstractMovementController](#).

6.9.1.6 setRearLeftWheelDirectionToForward()

```
void car::system::movement::controller::DummyMovementController::setRearLeftWheelDirectionTo←  
Forward ( ) [final], [override], [virtual]
```

Implements [car::system::movement::controller::AbstractMovementController](#).

6.9.1.7 setRearLeftWheelSpeed()

```
void car::system::movement::controller::DummyMovementController::setRearLeftWheelSpeed (
    const int speed ) [final], [override], [virtual]
```

Implements [car::system::movement::controller::AbstractMovementController](#).

6.9.1.8 setRearRightWheelDirectionToBackward()

```
void car::system::movement::controller::DummyMovementController::setRearRightWheelDirection↵
ToBackward ( ) [final], [override], [virtual]
```

Implements [car::system::movement::controller::AbstractMovementController](#).

6.9.1.9 setRearRightWheelDirectionToForward()

```
void car::system::movement::controller::DummyMovementController::setRearRightWheelDirection↵
ToForward ( ) [final], [override], [virtual]
```

Implements [car::system::movement::controller::AbstractMovementController](#).

6.9.1.10 setRearRightWheelSpeed()

```
void car::system::movement::controller::DummyMovementController::setRearRightWheelSpeed (
    const int speed ) [final], [override], [virtual]
```

Implements [car::system::movement::controller::AbstractMovementController](#).

6.9.1.11 setRearWheelsDirectionToBackward()

```
void car::system::movement::controller::DummyMovementController::setRearWheelsDirectionTo↵
Backward ( ) [final], [override], [virtual]
```

Implements [car::system::movement::controller::AbstractMovementController](#).

6.9.1.12 setRearWheelsDirectionToForward()

```
void car::system::movement::controller::DummyMovementController::setRearWheelsDirectionTo↵
Forward ( ) [final], [override], [virtual]
```

Implements [car::system::movement::controller::AbstractMovementController](#).

6.9.1.13 setRearWheelsSpeed()

```
void car::system::movement::controller::DummyMovementController::setRearWheelsSpeed (
    const int speed ) [final], [override], [virtual]
```

Implements [car::system::movement::controller::AbstractMovementController](#).

6.9.1.14 stop()

```
void car::system::movement::controller::DummyMovementController::stop ( ) [final], [override],
[virtual]
```

Implements [car::system::movement::controller::AbstractMovementController](#).

6.9.1.15 terminate()

```
void car::system::movement::controller::DummyMovementController::terminate ( ) [inline],
[final], [override], [virtual]
```

Implements [car::system::movement::controller::AbstractMovementController](#).

The documentation for this class was generated from the following files:

- include/car/system/movement/controller/[DummyMovementController.h](#)
- src/car/system/movement/controller/[DummyMovementController.cpp](#)

6.10 car::system::messaging::MessagingSystem::FirstMessageStruct Struct Reference

```
#include <MessagingSystem.h>
```

Public Attributes

- std::string [error_message](#)
- std::string [uuid](#)
- std::condition_variable [condition](#)

6.10.1 Member Data Documentation

6.10.1.1 condition

```
std::condition_variable car::system::messaging::MessagingSystem::FirstMessageStruct::condition
```

6.10.1.2 error_message

```
std::string car::system::messaging::MessagingSystem::FirstMessageStruct::error_message
```

6.10.1.3 uuid

```
std::string car::system::messaging::MessagingSystem::FirstMessageStruct::uuid
```

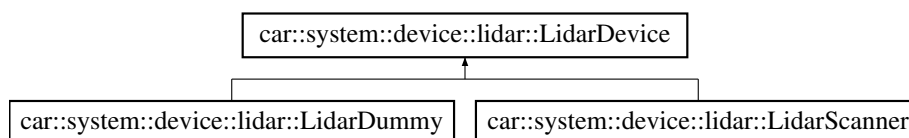
The documentation for this struct was generated from the following file:

- [include/car/system/messaging/MessagingSystem.h](#)

6.11 car::system::device::lidar::LidarDevice Class Reference

```
#include <LidarDevice.h>
```

Inheritance diagram for car::system::device::lidar::LidarDevice:



Public Member Functions

- `std::vector< Measure > getScanData () const`
- `virtual void start ()=0`
- `virtual void update ()=0`
- `virtual void stop ()=0`
- `virtual void initialize ()=0`
- `virtual void terminate ()=0`
- `virtual void disconnect ()=0`

Protected Member Functions

- `void setScanData (const std::vector< Measure > &scan_data)`

Protected Attributes

- `std::vector< Measure >` [scan_data_](#)

Friends

- class [DeviceManager](#)

6.11.1 Member Function Documentation

6.11.1.1 disconnect()

```
virtual void car::system::device::lidar::LidarDevice::disconnect ( ) [pure virtual]
```

Implemented in [car::system::device::lidar::LidarDummy](#), and [car::system::device::lidar::LidarScanner](#).

6.11.1.2 getScanData()

```
std::vector< Measure > car::system::device::lidar::LidarDevice::getScanData ( ) const [inline]
```

6.11.1.3 initialize()

```
virtual void car::system::device::lidar::LidarDevice::initialize ( ) [pure virtual]
```

Implemented in [car::system::device::lidar::LidarDummy](#), and [car::system::device::lidar::LidarScanner](#).

6.11.1.4 setScanData()

```
void car::system::device::lidar::LidarDevice::setScanData (
    const std::vector< Measure > & scan_data ) [inline], [protected]
```

6.11.1.5 start()

```
virtual void car::system::device::lidar::LidarDevice::start ( ) [pure virtual]
```

Implemented in [car::system::device::lidar::LidarDummy](#), and [car::system::device::lidar::LidarScanner](#).

6.11.1.6 stop()

```
virtual void car::system::device::lidar::LidarDevice::stop ( ) [pure virtual]
```

Implemented in [car::system::device::lidar::LidarDummy](#), and [car::system::device::lidar::LidarScanner](#).

6.11.1.7 terminate()

```
virtual void car::system::device::lidar::LidarDevice::terminate ( ) [pure virtual]
```

Implemented in [car::system::device::lidar::LidarDummy](#), and [car::system::device::lidar::LidarScanner](#).

6.11.1.8 update()

```
virtual void car::system::device::lidar::LidarDevice::update ( ) [pure virtual]
```

Implemented in [car::system::device::lidar::LidarDummy](#), and [car::system::device::lidar::LidarScanner](#).

6.11.2 Friends And Related Function Documentation

6.11.2.1 DeviceManager

```
friend class DeviceManager [friend]
```

6.11.3 Member Data Documentation

6.11.3.1 scan_data_

```
std::vector<Measure> car::system::device::lidar::LidarDevice::scan_data_ [protected]
```

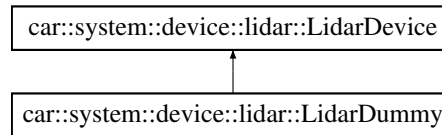
The documentation for this class was generated from the following file:

- [include/car/system/device/lidar/LidarDevice.h](#)

6.12 car::system::device::lidar::LidarDummy Class Reference

```
#include <LidarDummy.h>
```

Inheritance diagram for car::system::device::lidar::LidarDummy:



Public Member Functions

- [LidarDummy](#) ()
- void [start](#) () final override
- void [update](#) () final override
- void [stop](#) () final override
- void [initialize](#) () final override
- void [terminate](#) () final override
- void [disconnect](#) () final override

Additional Inherited Members

6.12.1 Constructor & Destructor Documentation

6.12.1.1 LidarDummy()

```
car::system::device::lidar::LidarDummy::LidarDummy ( ) [inline]
```

6.12.2 Member Function Documentation

6.12.2.1 disconnect()

```
void car::system::device::lidar::LidarDummy::disconnect ( ) [inline], [final], [override],  
[virtual]
```

Implements [car::system::device::lidar::LidarDevice](#).

6.12.2.2 initialize()

```
void car::system::device::lidar::LidarDummy::initialize ( ) [inline], [final], [override],  
[virtual]
```

Implements [car::system::device::lidar::LidarDevice](#).

6.12.2.3 start()

```
void car::system::device::lidar::LidarDummy::start ( ) [inline], [final], [override], [virtual]
```

Implements [car::system::device::lidar::LidarDevice](#).

6.12.2.4 stop()

```
void car::system::device::lidar::LidarDummy::stop ( ) [inline], [final], [override], [virtual]
```

Implements [car::system::device::lidar::LidarDevice](#).

6.12.2.5 terminate()

```
void car::system::device::lidar::LidarDummy::terminate ( ) [inline], [final], [override],  
[virtual]
```

Implements [car::system::device::lidar::LidarDevice](#).

6.12.2.6 update()

```
void car::system::device::lidar::LidarDummy::update ( ) [inline], [final], [override], [virtual]
```

Implements [car::system::device::lidar::LidarDevice](#).

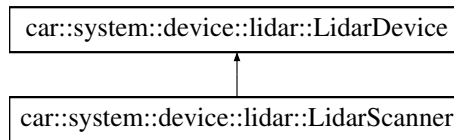
The documentation for this class was generated from the following file:

- [include/car/system/device/lidar/LidarDummy.h](#)

6.13 car::system::device::lidar::LidarScanner Class Reference

```
#include <LidarScanner.h>
```

Inheritance diagram for car::system::device::lidar::LidarScanner:



Public Member Functions

- [LidarScanner](#) (std::shared_ptr< [configuration::Configuration](#) > configuration, std::unique_ptr< RPLidar > lidar)
- void [start](#) () final override
- void [update](#) () final override
- void [stop](#) () final override
- void [initialize](#) () final override
- void [disconnect](#) () final override
- void [terminate](#) () final override

Static Public Member Functions

- static tl::expected< std::unique_ptr< [LidarScanner](#) >, std::string > [create](#) (std::shared_ptr< [configuration::Configuration](#) > configuration) noexcept

Private Attributes

- std::atomic_bool [running](#) = false
- std::shared_ptr< [configuration::Configuration](#) > [configuration_](#)
- std::vector< Measure > [scan_data_](#)
- std::unique_ptr< RPLidar > [lidar_](#)
- std::variant< std::function< std::vector< Measure >()>, nullptr_t > [scan_generator_](#) = nullptr
- std::mutex [scan_data_mutex_](#)

Additional Inherited Members

6.13.1 Constructor & Destructor Documentation

6.13.1.1 LidarScanner()

```
car::system::device::lidar::LidarScanner::LidarScanner (
    std::shared_ptr< configuration::Configuration > configuration,
    std::unique_ptr< RPLidar > lidar ) [inline]
```

6.13.2 Member Function Documentation

6.13.2.1 create()

```
static tl::expected< std::unique_ptr< LidarScanner >, std::string > car::system::device↵  
::lidar::LidarScanner::create (   
    std::shared_ptr< configuration::Configuration > configuration ) [inline], [static],  
[noexcept]
```

6.13.2.2 disconnect()

```
void car::system::device::lidar::LidarScanner::disconnect ( ) [inline], [final], [override],  
[virtual]
```

Implements [car::system::device::lidar::LidarDevice](#).

6.13.2.3 initialize()

```
void car::system::device::lidar::LidarScanner::initialize ( ) [inline], [final], [override],  
[virtual]
```

Implements [car::system::device::lidar::LidarDevice](#).

6.13.2.4 start()

```
void car::system::device::lidar::LidarScanner::start ( ) [inline], [final], [override], [virtual]
```

Implements [car::system::device::lidar::LidarDevice](#).

6.13.2.5 stop()

```
void car::system::device::lidar::LidarScanner::stop ( ) [inline], [final], [override], [virtual]
```

Implements [car::system::device::lidar::LidarDevice](#).

6.13.2.6 terminate()

```
void car::system::device::lidar::LidarScanner::terminate ( ) [inline], [final], [override],  
[virtual]
```

Implements [car::system::device::lidar::LidarDevice](#).

6.13.2.7 update()

```
void car::system::device::lidar::LidarScanner::update ( ) [inline], [final], [override],  
[virtual]
```

Implements [car::system::device::lidar::LidarDevice](#).

6.13.3 Member Data Documentation

6.13.3.1 configuration_

```
std::shared_ptr<configuration::Configuration> car::system::device::lidar::LidarScanner::configuration↔  
_ [private]
```

6.13.3.2 lidar_

```
std::unique_ptr<RPLidar> car::system::device::lidar::LidarScanner::lidar_ [private]
```

6.13.3.3 running

```
std::atomic_bool car::system::device::lidar::LidarScanner::running = false [private]
```

6.13.3.4 scan_data_

```
std::vector<Measure> car::system::device::lidar::LidarScanner::scan_data_ [private]
```

6.13.3.5 scan_data_mutex_

```
std::mutex car::system::device::lidar::LidarScanner::scan_data_mutex_ [private]
```

6.13.3.6 scan_generator_

```
std::variant<std::function<std::vector<Measure>()>, nullptr_t> car::system::device::lidar↔  
::LidarScanner::scan_generator_ = nullptr [private]
```

The documentation for this class was generated from the following file:

- include/car/system/device/lidar/[LidarScanner.h](#)

6.14 car::system::messaging::MessagingSystem Class Reference

```
#include <MessagingSystem.h>
```

Classes

- struct [FirstMessageStruct](#)

Public Member Functions

- [MessagingSystem](#) ()
- void [initialize](#) (std::shared_ptr< [configuration::Configuration](#) > configuration)
Initializes the use of Websockets and initializes the Signals.
- void [initializeWebSocket](#) ()
Creates a new WebSocket object for use.
- const tl::expected< nullptr_t, std::string > [tryConnect](#) ()
Attempts to connect to the WebSocket server and retrieves the first message from the WebSocket (Should be UUID)
- void [stop](#) ()
- void [terminate](#) ()
- void [setConfiguration](#) (std::shared_ptr< [configuration::Configuration](#) > configuration)
- nod::signal< void(const std::string, const rapidjson::Document &);> & [getCommandSignal](#) ()
- nod::signal< void(const std::string, const rapidjson::Document &);> & [getSelectionSignal](#) ()
- nod::signal< void(const std::string)> & [getMessageSignal](#) ()
- nod::signal< void(const std::string)> & [getDisconnectSignal](#) ()
- void [onMessageCallback](#) (const ix::WebSocketMessagePtr &msg) const
- void [onDisconnect](#) (const std::string)
- const std::string [getUUID](#) () const
- void [handleMessage](#) (const std::string &message) const
Sends out signals depending on the type of message.
- void [sendMessage](#) (const std::string &message)
- void [onFirstMessage](#) (const ix::WebSocketMessagePtr &msg, [FirstMessageStruct](#) &first_message_struct)
Actually retrieves the First Message from the WebSocket to put into [FirstMessageStruct](#).
- const bool [isConnected](#) () const

Public Attributes

- `nod::signal< void(std::string)>` [on_disconnect_signal_](#)
- `nod::signal< void(const std::string)>` [message_signal_](#)
- `nod::signal< void(const std::string, const rapidjson::Document &)>` [command_signal_](#)
- `nod::signal< void(const std::string, const rapidjson::Document &)>` [selection_signal_](#)

Private Member Functions

- `tl::expected< std::string, std::string >` [getFirstMessage](#) ()
Waits and retrieves the first message when connecting to a websocket.

Private Attributes

- `std::shared_ptr< configuration::Configuration >` [configuration_](#)
- `std::unique_ptr< ix::WebSocket >` [websocket_](#)
- `std::string` [websocket_url_](#)
- `std::string` [uuid_](#)
- `bool` [connected_](#) = false

6.14.1 Constructor & Destructor Documentation

6.14.1.1 MessagingSystem()

```
car::system::messaging::MessagingSystem::MessagingSystem ( )
```

6.14.2 Member Function Documentation

6.14.2.1 getCommandSignal()

```
nod::signal< void(const std::string, const rapidjson::Document &)> & car::system::messaging↵  
::MessagingSystem::getCommandSignal ( ) [inline]
```

6.14.2.2 getDisconnectSignal()

```
nod::signal< void(const std::string)> & car::system::messaging::MessagingSystem::getDisconnect↵  
Signal ( ) [inline]
```

6.14.2.3 getFirstMessage()

```
tl::expected< std::string, std::string > car::system::messaging::MessagingSystem::getFirstMessage ( ) [private]
```

Waits and retrieves the first message when connecting to a websocket.

Returns

tl::expected<std::string, std::string>

6.14.2.4 getMessageSignal()

```
nod::signal< void(const std::string)> & car::system::messaging::MessagingSystem::getMessageSignal ( ) [inline]
```

6.14.2.5 getSelectionSignal()

```
nod::signal< void(const std::string, const rapidjson::Document &)> & car::system::messaging::MessagingSystem::getSelectionSignal ( ) [inline]
```

6.14.2.6 getUUID()

```
const std::string car::system::messaging::MessagingSystem::getUUID ( ) const [inline]
```

6.14.2.7 handleMessage()

```
void car::system::messaging::MessagingSystem::handleMessage (
    const std::string & message ) const
```

Sends out signals depending on the type of message.

Parameters

<i>message</i>	
----------------	--

6.14.2.8 initialize()

```
void car::system::messaging::MessagingSystem::initialize (
    std::shared_ptr< configuration::Configuration > configuration )
```

Initializes the use of Websockets and initializes the Signals.

Parameters

<i>configuration</i>	
----------------------	--

6.14.2.9 initializeWebSocket()

```
void car::system::messaging::MessagingSystem::initializeWebSocket ( )
```

Creates a new WebSocket object for use.

6.14.2.10 isConnected()

```
const bool car::system::messaging::MessagingSystem::isConnected ( ) const [inline]
```

6.14.2.11 onDisconnect()

```
void car::system::messaging::MessagingSystem::onDisconnect (
    const std::string message )
```

6.14.2.12 onFirstMessage()

```
void car::system::messaging::MessagingSystem::onFirstMessage (
    const ix::WebSocketMessagePtr & msg,
    FirstMessageStruct & first_message_struct )
```

Actually retrieves the First Message from the WebSocket to put into [FirstMessageStruct](#).

Parameters

<i>msg</i>	
<i>first_message_struct</i>	

6.14.2.13 onMessageCallback()

```
void car::system::messaging::MessagingSystem::onMessageCallback (
    const ix::WebSocketMessagePtr & msg ) const
```

6.14.2.14 sendMessage()

```
void car::system::messaging::MessagingSystem::sendMessage (
    const std::string & message )
```

6.14.2.15 setConfiguration()

```
void car::system::messaging::MessagingSystem::setConfiguration (
    std::shared_ptr< configuration::Configuration > configuration )
```

6.14.2.16 stop()

```
void car::system::messaging::MessagingSystem::stop ( )
```

6.14.2.17 terminate()

```
void car::system::messaging::MessagingSystem::terminate ( )
```

6.14.2.18 tryConnect()

```
const tl::expected< nullptr_t, std::string > car::system::messaging::MessagingSystem::try↵
Connect ( )
```

Attempts to connect to the Websocket server and retrieves the first message from the Websocket (Should be UUID)

Returns

```
const tl::expected<nullptr_t, std::string>
```

6.14.3 Member Data Documentation

6.14.3.1 command_signal_

```
nod::signal<void(const std::string, const rapidjson::Document&)> car::system::messaging::↔  
MessagingSystem::command_signal_
```

6.14.3.2 configuration_

```
std::shared_ptr<configuration::Configuration> car::system::messaging::MessagingSystem::configuration↔  
_ [private]
```

6.14.3.3 connected_

```
bool car::system::messaging::MessagingSystem::connected_ = false [private]
```

6.14.3.4 message_signal_

```
nod::signal<void(const std::string)> car::system::messaging::MessagingSystem::message_signal↔  
_
```

6.14.3.5 on_disconnect_signal_

```
nod::signal<void(std::string)> car::system::messaging::MessagingSystem::on_disconnect_signal↔  
_
```

6.14.3.6 selection_signal_

```
nod::signal<void(const std::string, const rapidjson::Document&)> car::system::messaging::↔  
MessagingSystem::selection_signal_
```

6.14.3.7 uuid_

```
std::string car::system::messaging::MessagingSystem::uuid_ [private]
```

6.14.3.8 websocket_

```
std::unique_ptr<ix::WebSocket> car::system::messaging::MessagingSystem::websocket_ [private]
```

6.14.3.9 websocket_url_

```
std::string car::system::messaging::MessagingSystem::websocket_url_ [private]
```

The documentation for this class was generated from the following files:

- include/car/system/messaging/[MessagingSystem.h](#)
- src/car/system/messaging/[MessagingSystem.cpp](#)

6.15 car::system::movement::MovementSystem Class Reference

```
#include <MovementSystem.h>
```

Public Member Functions

- [MovementSystem](#) (std::unique_ptr< [AbstractMovementController](#) > movement_controller)
- void [initialize](#) ()
- void [start](#) ()
- void [stop](#) ()
- void [terminate](#) ()
- void [setRearWheelsSpeed](#) (const int speed) const
- void [setRearLeftWheelSpeed](#) (const int speed) const
- void [setRearRightWheelSpeed](#) (const int speed) const
- void [setFrontWheelsAngle](#) (const float angle) const
- void [setCameraServo1Angle](#) (const float angle) const
- void [setCameraServo2Angle](#) (const float angle) const
- void [setRearWheelsDirectionToForward](#) () const
- void [setRearLeftWheelDirectionToForward](#) () const
- void [setRearRightWheelDirectionToForward](#) () const
- void [setRearWheelsDirectionToBackward](#) () const
- void [setRearLeftWheelDirectionToBackward](#) () const
- void [setRearRightWheelDirectionToBackward](#) () const
- [~MovementSystem](#) ()

Private Attributes

- std::unique_ptr< [AbstractMovementController](#) > *movement_controller*

6.15.1 Constructor & Destructor Documentation

6.15.1.1 MovementSystem()

```
car::system::movement::MovementSystem::MovementSystem (
    std::unique_ptr< AbstractMovementController > movement_controller ) [inline]
```

6.15.1.2 ~MovementSystem()

```
car::system::movement::MovementSystem::~~MovementSystem ( ) [inline]
```

6.15.2 Member Function Documentation

6.15.2.1 initialize()

```
void car::system::movement::MovementSystem::initialize ( ) [inline]
```

6.15.2.2 setCameraServo1Angle()

```
void car::system::movement::MovementSystem::setCameraServo1Angle (
    const float angle ) const [inline]
```

6.15.2.3 setCameraServo2Angle()

```
void car::system::movement::MovementSystem::setCameraServo2Angle (
    const float angle ) const [inline]
```

6.15.2.4 setFrontWheelsAngle()

```
void car::system::movement::MovementSystem::setFrontWheelsAngle (
    const float angle ) const [inline]
```

6.15.2.5 setRearLeftWheelDirectionToBackward()

```
void car::system::movement::MovementSystem::setRearLeftWheelDirectionToBackward ( ) const
[inline]
```

6.15.2.6 setRearLeftWheelDirectionToForward()

```
void car::system::movement::MovementSystem::setRearLeftWheelDirectionToForward ( ) const [inline]
```

6.15.2.7 setRearLeftWheelSpeed()

```
void car::system::movement::MovementSystem::setRearLeftWheelSpeed (
    const int speed ) const [inline]
```

6.15.2.8 setRearRightWheelDirectionToBackward()

```
void car::system::movement::MovementSystem::setRearRightWheelDirectionToBackward ( ) const
[inline]
```

6.15.2.9 setRearRightWheelDirectionToForward()

```
void car::system::movement::MovementSystem::setRearRightWheelDirectionToForward ( ) const
[inline]
```

6.15.2.10 setRearRightWheelSpeed()

```
void car::system::movement::MovementSystem::setRearRightWheelSpeed (
    const int speed ) const [inline]
```

6.15.2.11 setRearWheelsDirectionToBackward()

```
void car::system::movement::MovementSystem::setRearWheelsDirectionToBackward ( ) const [inline]
```

6.15.2.12 setRearWheelsDirectionToForward()

```
void car::system::movement::MovementSystem::setRearWheelsDirectionToForward ( ) const [inline]
```

6.15.2.13 setRearWheelsSpeed()

```
void car::system::movement::MovementSystem::setRearWheelsSpeed (
    const int speed ) const [inline]
```

6.15.2.14 start()

```
void car::system::movement::MovementSystem::start ( ) [inline]
```

6.15.2.15 stop()

```
void car::system::movement::MovementSystem::stop ( ) [inline]
```

6.15.2.16 terminate()

```
void car::system::movement::MovementSystem::terminate ( ) [inline]
```

6.15.3 Member Data Documentation

6.15.3.1 movement_controller

```
std::unique_ptr<AbstractMovementController> car::system::movement::MovementSystem::movement_↔
controller [private]
```

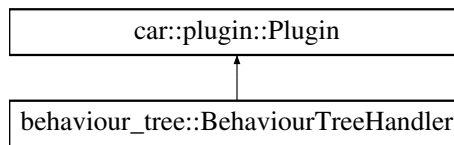
The documentation for this class was generated from the following file:

- include/car/system/movement/[MovementSystem.h](#)

6.16 car::plugin::Plugin Class Reference

```
#include <Plugin.h>
```

Inheritance diagram for car::plugin::Plugin:



Public Member Functions

- virtual void [initialize](#) (std::shared_ptr< [car::system::CarSystem](#) > car_system)=0
- virtual void [update](#) ()=0
- virtual void [stop](#) ()=0
- virtual std::string [getName](#) ()=0

6.16.1 Member Function Documentation

6.16.1.1 getName()

```
virtual std::string car::plugin::Plugin::getName ( ) [pure virtual]
```

Implemented in [behaviour_tree::BehaviourTreeHandler](#).

6.16.1.2 initialize()

```
virtual void car::plugin::Plugin::initialize (
    std::shared_ptr< car::system::CarSystem > car_system ) [pure virtual]
```

Implemented in [behaviour_tree::BehaviourTreeHandler](#).

6.16.1.3 stop()

```
virtual void car::plugin::Plugin::stop ( ) [pure virtual]
```

Implemented in [behaviour_tree::BehaviourTreeHandler](#).

6.16.1.4 update()

```
virtual void car::plugin::Plugin::update ( ) [pure virtual]
```

Implemented in [behaviour_tree::BehaviourTreeHandler](#).

The documentation for this class was generated from the following file:

- include/car/plugin/[Plugin.h](#)

6.17 car::plugin::PluginManager Class Reference

```
#include <PluginManager.h>
```

Public Member Functions

- void [initialize](#) (std::shared_ptr< [system::CarSystem](#) > car_system)
- void [update](#) ()
- void [stop](#) ()
- void [terminate](#) ()
- void [addPlugin](#) (std::shared_ptr< [Plugin](#) > plugin)
- template<typename T >
std::shared_ptr< T > [getPlugin](#) ()

Private Attributes

- std::vector< std::shared_ptr< [Plugin](#) > > [plugins](#)

6.17.1 Member Function Documentation

6.17.1.1 addPlugin()

```
void car::plugin::PluginManager::addPlugin (
    std::shared_ptr< Plugin > plugin ) [inline]
```

6.17.1.2 getPlugin()

```
template<typename T >
std::shared_ptr< T > car::plugin::PluginManager::getPlugin ( ) [inline]
```

6.17.1.3 initialize()

```
void car::plugin::PluginManager::initialize (
    std::shared_ptr< system::CarSystem > car_system ) [inline]
```

6.17.1.4 stop()

```
void car::plugin::PluginManager::stop ( ) [inline]
```

6.17.1.5 terminate()

```
void car::plugin::PluginManager::terminate ( ) [inline]
```

6.17.1.6 update()

```
void car::plugin::PluginManager::update ( ) [inline]
```

6.17.2 Member Data Documentation

6.17.2.1 plugins

```
std::vector<std::shared_ptr<Plugin> > car::plugin::PluginManager::plugins [private]
```

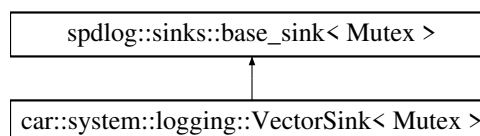
The documentation for this class was generated from the following file:

- include/car/plugin/[PluginManager.h](#)

6.18 car::system::logging::VectorSink< Mutex > Class Template Reference

```
#include <VectorSink.h>
```

Inheritance diagram for car::system::logging::VectorSink< Mutex >:



Public Member Functions

- [VectorSink](#) (int [max_lines](#))
- void [sink_it_](#) (const spdlog::details::log_msg &msg) override
- void [flush_](#) () override
- const std::vector< std::string > & [get_log_messages](#) () const

Private Attributes

- const int [max_lines](#)
- std::vector< std::string > [log_messages](#)

6.18.1 Constructor & Destructor Documentation

6.18.1.1 VectorSink()

```
template<typename Mutex >
car::system::logging::VectorSink< Mutex >::VectorSink (
    int max_lines ) [inline]
```

6.18.2 Member Function Documentation

6.18.2.1 flush_()

```
template<typename Mutex >
void car::system::logging::VectorSink< Mutex >::flush_ ( ) [inline], [override]
```

6.18.2.2 get_log_messages()

```
template<typename Mutex >
const std::vector< std::string > & car::system::logging::VectorSink< Mutex >::get_log_↵
messages ( ) const [inline]
```

6.18.2.3 sink_it_()

```
template<typename Mutex >
void car::system::logging::VectorSink< Mutex >::sink_it_ (
    const spdlog::details::log_msg & msg ) [inline], [override]
```

6.18.3 Member Data Documentation

6.18.3.1 log_messages

```
template<typename Mutex >  
std::vector<std::string> car::system::logging::VectorSink< Mutex >::log_messages [private]
```

6.18.3.2 max_lines

```
template<typename Mutex >  
const int car::system::logging::VectorSink< Mutex >::max_lines [private]
```

The documentation for this class was generated from the following file:

- [include/car/system/logging/VectorSink.h](#)

Chapter 7

File Documentation

7.1 include/behaviour_tree/BehaviourTreeHandler.hpp File Reference

```
#include <string>
#include <vector>
#include <nod/nod.hpp>
#include "utils/Utility.hpp"
#include "car/plugin/Plugin.h"
#include "behaviour_tree/BehaviourTreeParser.hpp"
#include "behaviour_tree/node/custom/CarCustomNodeParser.hpp"
#include "CarContext.hpp"
```

Classes

- class [behaviour_tree::BehaviourTreeHandler](#)

Namespaces

- namespace [behaviour_tree](#)

7.2 BehaviourTreeHandler.hpp

[Go to the documentation of this file.](#)

```
1 #ifndef BEHAVIOURTREEHANDLER_HPP
2 #define BEHAVIOURTREEHANDLER_HPP
3
4 #pragma once
5
6 #include <string>
7 #include <vector>
8
9 #include <nod/nod.hpp>
10
11 #include "utils/Utility.hpp"
12
13 #include "car/plugin/Plugin.h"
14
15 #include "behaviour_tree/BehaviourTreeParser.hpp"
16 #include "behaviour_tree/node/custom/CarCustomNodeParser.hpp"
17
```

```

18 #include "CarContext.hpp"
19
20 namespace behaviour_tree
21 {
22     class BehaviourTreeHandler : public car::plugin::Plugin
23     {
24     public:
25         void initialize(std::shared_ptr<car::system::CarSystem> car_system) final override
26         {
27             this->car_system = car_system;
28             // The BehaviourTreeParser does not come with a CustomNodeParser since each program can have
29             // a different set of Action nodes
30
31             BehaviourTreeParser::instance().setCustomNodeParser(std::make_shared<node::custom::CarCustomNodeParser>(CarCustomNodeP
32
33             this->car_system->getMessagingSystem()->getCommandSignal().connect(std::bind(&BehaviourTreeHandler::handleCommand,
34             this, std::placeholders::_1, std::placeholders::_2));
35         }
36
37         void handleCommand(const std::string message, const rapidjson::Document &message_json)
38         {
39             const std::string command = message_json["command"].GetString();
40             if (command != "behaviour_tree")
41             {
42                 spdlog::error(R"(The property "command" does not match "behaviour_tree", {})", command);
43                 return;
44             }
45             if (!message_json.HasMember("action") || !message_json["action"].IsString())
46             {
47                 spdlog::error(R"(The property "action" does not exist in the given json.)");
48                 return;
49             }
50             const std::string action = message_json["action"].GetString();
51             switch (utils::hash(action))
52             {
53             case utils::hash("set"):
54             {
55                 this->setBehaviourTree(message_json);
56                 break;
57             }
58             case utils::hash("start"):
59             {
60                 this->startBehaviourTree();
61                 break;
62             }
63             case utils::hash("stop"):
64             {
65                 this->stopBehaviourTree();
66                 break;
67             }
68             default:
69             {
70                 spdlog::error(R"(The property "action" does not match "set" or "start", {})", action);
71                 break;
72             }
73             };
74         }
75
76         void setBehaviourTree(const rapidjson::Document &message_json)
77         {
78             if (!message_json.HasMember("data") || !message_json["data"].IsString())
79             {
80                 spdlog::error(R"(The property "data" does not exist in the given json.)");
81                 return;
82             }
83             try
84             {
85                 auto maybe_behaviour_tree =
86                 BehaviourTreeParser::instance().parseXML(message_json["data"].GetString());
87                 if (!maybe_behaviour_tree.has_value())
88                 {
89                     spdlog::error(R"(Unable to parse the given behaviour tree | {})",
90                     maybe_behaviour_tree.error());
91                     return;
92                 }
93                 auto &behaviour_tree = maybe_behaviour_tree.value();
94                 spdlog::info("Behaviour tree parsed successfully | {}", behaviour_tree->toString());
95                 this->_setBehaviourTree(behaviour_tree);
96             }
97             catch (std::exception &e)
98             {
99                 spdlog::error("An error has occurred while parsing the given behaviour tree: {}",
100                 e.what());
101             }
102         }
103
104         void startBehaviourTree()
105         {
106             assert(this->car_system != nullptr);
107         }
108     };
109 }

```

```

98         if (this->behaviour_tree == nullptr)
99         {
100             spdlog::error("The Behaviour tree has not been set");
101             return;
102         }
103         this->behaviour_tree->resetCycles();
104         this->tick_count = 0;
105         std::shared_ptr<Context> context = std::make_shared<CarContext>(this->behaviour_tree,
this->car_system);
106         this->context = context;
107         spdlog::info("Starting the given Behaviour tree");
108     }
109
110     void stopBehaviourTree()
111     {
112         assert(this->car_system != nullptr);
113         this->context = nullptr;
114         spdlog::info("Stopped any Behaviour Tree context");
115     }
116
117     void update() final override
118     {
119         if (this->context == nullptr)
120         {
121             return;
122         }
123         if (this->context->canRun())
124         {
125             const std::chrono::time_point<std::chrono::steady_clock> now =
std::chrono::steady_clock::now();
126             // TODO:
127             if (now - this->last_connected >=
this->car_system->getConfiguration()->behaviour_tree_update_ms_interval) {
128                 this->context->update(this->tick_count);
129                 this->tick_count++;
130                 this->last_connected = now;
131             }
132         }
133         else
134         {
135             this->context = nullptr;
136         }
137     }
138
139     void stop() final override
140     {
141         this->context = nullptr;
142     }
143
144     std::string getName() final override
145     {
146         return "BehaviourTreeHandler";
147     }
148
149     void _setBehaviourTree(std::shared_ptr<BehaviourTree> behaviour_tree)
150     {
151         this->behaviour_tree = behaviour_tree;
152     }
153
154 private:
155     std::shared_ptr<car::system::CarSystem> car_system;
156
157     std::shared_ptr<BehaviourTree> behaviour_tree;
158     std::shared_ptr<Context> context;
159
160     int tick_count = 0;
161
162     // This is initialized as 0
163     std::chrono::time_point<std::chrono::steady_clock> last_connected;
164 };
165 } // namespace behaviour_tree
166
167 #endif

```

7.3 include/behaviour_tree/CarContext.hpp File Reference

```

#include "car/system/CarSystem.h"
#include "behaviour_tree/Context.h"

```

Classes

- class [behaviour_tree::CarContext](#)

Namespaces

- namespace [behaviour_tree](#)

7.4 CarContext.hpp

[Go to the documentation of this file.](#)

```

1 #ifndef BEHAVIOUR_TREE_CARCONTEXT_HPP
2 #define BEHAVIOUR_TREE_CARCONTEXT_HPP
3
4 #pragma once
5
6 #include "car/system/CarSystem.h"
7 #include "behaviour_tree/Context.h"
8
9 namespace behaviour_tree
10 {
11     class CarContext : public Context
12     {
13     public:
14         CarContext(std::shared_ptr<BehaviourTree> behaviour_tree, std::shared_ptr<car::system::CarSystem>
car_system) : Context(std::move(behaviour_tree)), car_system(std::move(car_system))
15         {
16         }
17
18         std::shared_ptr<car::system::CarSystem> getCarSystem() const
19         {
20             return this->car_system;
21         }
22
23         void _() override{};
24
25     private:
26         std::shared_ptr<car::system::CarSystem> car_system;
27     };
28 }
29
30 #endif

```

7.5 include/car/configuration/Configuration.h File Reference

```

#include <chrono>
#include <optional>
#include <string>
#include <tl/expected.hpp>

```

Classes

- struct [car::configuration::Configuration](#)

Namespaces

- namespace [car](#)
- namespace [car::configuration](#)

7.6 Configuration.h

[Go to the documentation of this file.](#)

```

1 #ifndef CONFIGURATION_H
2 #define CONFIGURATION_H
3
4 #pragma once
5
6 #include <chrono>
7 #include <optional>
8 #include <string>
9
10 #include <tl/expected.hpp>
11
12 namespace car::configuration
13 {
14     struct Configuration
15     {
16         std::string host = "127.0.0.1:3000";
17
18         int camera_index = 0;
19         void setCameraFps(const int camera_fps)
20         {
21             this->camera_fps = camera_fps;
22             this->camera_fps_interval = 1000 / camera_fps;
23         }
24         const int getCameraFpsInterval() { return this->camera_fps_interval; }
25         bool use_camera = true;
26
27         std::string lidar_port = "";
28         bool use_lidar = true;
29
30         std::chrono::milliseconds behaviour_tree_update_ms_interval = std::chrono::milliseconds(100);
31
32     private:
33         int camera_fps = 60;
34         int camera_fps_interval = 1000;
35     };
36 };
37
38 #endif

```

7.7 include/car/plugin/Plugin.h File Reference

```

#include <string>
#include <memory>

```

Classes

- class [car::plugin::Plugin](#)

Namespaces

- namespace [car](#)
- namespace [car::system](#)
- namespace [car::plugin](#)

7.8 Plugin.h

[Go to the documentation of this file.](#)

```
1 #ifndef PLUGIN_H
2 #define PLUGIN_H
3
4 #pragma once
5
6 #include <string>
7 #include <memory>
8
9 namespace car::system
10 {
11     class CarSystem;
12 }
13
14 namespace car::plugin
15 {
16     class Plugin
17     {
18     public:
19         virtual void initialize(std::shared_ptr<car::system::CarSystem> car_system) = 0;
20         virtual void update() = 0;
21         virtual void stop() = 0;
22         virtual std::string getName() = 0;
23     };
24 }
25
26 #endif
```

7.9 include/car/plugin/PluginManager.h File Reference

```
#include <vector>
#include <memory>
#include "utils/Utility.hpp"
#include "utils/TypeName.hpp"
#include "Plugin.h"
```

Classes

- class [car::plugin::PluginManager](#)

Namespaces

- namespace [car](#)
- namespace [car::system](#)
- namespace [car::plugin](#)

7.10 PluginManager.h

[Go to the documentation of this file.](#)

```
1 #ifndef PLUGIN_MANAGER_H
2 #define PLUGIN_MANAGER_H
3
4 #pragma once
5
6 #include <vector>
7 #include <memory>
8
9 #include "utils/Utility.hpp"
```

```

10 #include "utils/TypeName.hpp"
11
12 #include "Plugin.h"
13
14 namespace car::system
15 {
16     class CarSystem;
17 }
18
19 namespace car::plugin
20 {
21     class PluginManager
22     {
23     public:
24         void initialize(std::shared_ptr<system::CarSystem> car_system)
25         {
26             for (std::shared_ptr<Plugin>& plugin : this->plugins)
27             {
28                 plugin->initialize(car_system);
29             }
30         }
31
32         void update()
33         {
34             for (std::shared_ptr<Plugin>& plugin : this->plugins)
35             {
36                 plugin->update();
37             }
38         }
39
40         void stop()
41         {
42             for (std::shared_ptr<Plugin>& plugin : this->plugins)
43             {
44                 plugin->stop();
45             }
46         }
47
48         void terminate()
49         {
50             this->stop();
51         }
52
53         void addPlugin(std::shared_ptr<Plugin> plugin)
54         {
55             this->plugins.push_back(plugin);
56         }
57
58         template<typename T>
59         std::shared_ptr<T> getPlugin()
60         {
61             static_assert(std::is_base_of<Plugin, T>::value, "T must be a Plugin");
62             std::string type_name = std::string(utils::TypeName<T>());
63             type_name = utils::getStringAfterLastColon(type_name);
64
65             for (std::shared_ptr<Plugin>& plugin : this->plugins)
66             {
67                 if (plugin->getName() == type_name)
68                 {
69                     return plugin;
70                 }
71             }
72
73             return nullptr;
74         }
75
76     private:
77         std::vector<std::shared_ptr<Plugin>> plugins;
78     };
79 }
80
81 #endif

```

7.11 include/car/system/CarSystem.h File Reference

```

#include <memory>
#include "car/configuration/Configuration.h"
#include "car/system/device/DeviceManager.h"
#include "car/system/messaging/MessagingSystem.h"

```

```
#include "car/system/movement/MovementSystem.h"
#include "car/plugin/PluginManager.h"
```

Classes

- class [car::system::CarSystem](#)

Namespaces

- namespace [car](#)
- namespace [car::system](#)

7.12 CarSystem.h

[Go to the documentation of this file.](#)

```
1 #ifndef CARSYSTEM_H
2 #define CARSYSTEM_H
3
4 #pragma once
5
6 #include <memory>
7
8 #include "car/configuration/Configuration.h"
9
10 #include "car/system/device/DeviceManager.h"
11 #include "car/system/messaging/MessagingSystem.h"
12 #include "car/system/movement/MovementSystem.h"
13
14 #include "car/plugin/PluginManager.h"
15
16 using namespace car::configuration;
17 using namespace car::plugin;
18 using namespace car::system::device;
19 using namespace car::system::messaging;
20 using namespace car::system::movement;
21
22 namespace car::system
23 {
24     // Make sure this is stored as a shared_ptr
25     class CarSystem : public std::enable_shared_from_this<CarSystem>
26     {
27     public:
28         CarSystem(
29             std::shared_ptr<Configuration> configuration,
30             std::unique_ptr<DeviceManager> device_manager,
31             std::unique_ptr<MessagingSystem> messaging_system,
32             std::unique_ptr<MovementSystem> movement_system,
33             std::unique_ptr<PluginManager> plugin_manager);
34
35         void initialize();
36         void reload();
37
38         void start();
39         void stop();
40
41         tl::expected<nullptr_t, std::string> tryConnect();
42         void disconnect();
43
44         void terminate();
45
46         void update();
47
48         const std::shared_ptr<Configuration> getConfiguration() const { return this->configuration_; };
49         void setConfiguration(std::shared_ptr<Configuration> configuration);
50
51         DeviceManager *getDeviceManager() const
52         {
53             return this->device_manager_.get();
54         }
55     }
```

```

56     MessagingSystem *getMessagingSystem() const
57     {
58         return this->messaging_system_.get();
59     }
60
61     MovementSystem *getMovementSystem() const
62     {
63         return this->movement_system_.get();
64     }
65
66     template <typename T>
67     const std::shared_ptr<T> getPlugin() const { return this->plugin_manager_->getPlugin<T>(); }
68
69     private:
70         void sendData();
71
72         std::shared_ptr<Configuration> configuration_;
73
74         const std::unique_ptr<DeviceManager> device_manager_;
75         const std::unique_ptr<MessagingSystem> messaging_system_;
76         const std::unique_ptr<MovementSystem> movement_system_;
77         const std::unique_ptr<PluginManager> plugin_manager_;
78
79         bool initialized = false;
80         bool started = false;
81     };
82 }
83
84 #endif

```

7.13 include/car/system/device/CameraDevice.h File Reference

```

#include <vector>
#include <tl/expected.hpp>
#include <opencv2/opencv.hpp>
#include "car/configuration/Configuration.h"

```

Classes

- class [car::system::device::CameraDevice](#)

Namespaces

- namespace [car](#)
- namespace [car::system](#)
- namespace [car::system::device](#)

7.14 CameraDevice.h

[Go to the documentation of this file.](#)

```

1 #ifndef CAMERADEVICE_H
2 #define CAMERADEVICE_H
3
4 #pragma once
5
6 #include <vector>
7
8 #include <tl/expected.hpp>
9 #include <opencv2/opencv.hpp>
10
11 #include "car/configuration/Configuration.h"
12
13 namespace car::system::device

```

```

14 {
15     class DeviceManager;
16     class CameraDevice
17     {
18     public:
19         CameraDevice(std::shared_ptr<configuration::Configuration> configuration) :
            configuration(configuration) {}
20
21         CameraDevice(const CameraDevice&) = delete;
22         CameraDevice& operator=(const CameraDevice&) = delete;
23
24         CameraDevice(CameraDevice&&) = delete;
25         CameraDevice& operator=(CameraDevice&&) = delete;
26
27         ~CameraDevice() = default;
28
29     public:
30         [[nodiscard]] static tl::expected<std::unique_ptr<CameraDevice>, std::string>
            create(std::shared_ptr<configuration::Configuration> configuration);
31         std::string getFrameBuffer() const;
32
33     protected:
34         void start();
35         void update();
36         void stop();
37         void disconnect();
38         void terminate();
39
40         friend class DeviceManager;
41
42     private:
43         std::shared_ptr<configuration::Configuration> configuration;
44
45         std::unique_ptr<cv::VideoCapture> camera_;
46
47         bool connected_ = false;
48         std::string frame_buffer_;
49
50         std::mutex camera_mutex_;
51
52         std::chrono::steady_clock::time_point last;
53     };
54 }
55
56 #endif

```

7.15 include/car/system/device/DeviceManager.h File Reference

```

#include <memory>
#include <tl/expected.hpp>
#include "car/configuration/Configuration.h"
#include "CameraDevice.h"
#include "lidar/LidarDevice.h"
#include "lidar/LidarScanner.h"

```

Classes

- class `car::system::device::DeviceManager`

Namespaces

- namespace `car`
- namespace `car::system`
- namespace `car::system::device`

7.16 DeviceManager.h

[Go to the documentation of this file.](#)

```

1  #ifndef DEVICE_MANAGER_H
2  #define DEVICE_MANAGER_H
3
4  #pragma once
5
6  #include <memory>
7
8  #include <tl/expected.hpp>
9
10 #include "car/configuration/Configuration.h"
11
12 #include "CameraDevice.h"
13 #include "lidar/LidarDevice.h"
14 #include "lidar/LidarScanner.h"
15
16 using namespace car::configuration;
17
18 namespace car::system
19 {
20     class CarSystem;
21 }
22
23 namespace car::system::device
24 {
25     class DeviceManager {
26     public:
27         [[nodiscard]] static tl::expected<std::unique_ptr<DeviceManager>, std::string>
28         create(std::shared_ptr<Configuration> configuration);
29
30         DeviceManager(std::unique_ptr<CameraDevice> camera_device, std::unique_ptr<lidar::LidarDevice>
31         lidar_device) :
32             camera_device_(std::move(camera_device)),
33             lidar_device_(std::move(lidar_device))
34         {
35         }
36
37         CameraDevice* getCameraDevice() {
38             return this->camera_device_.get();
39         }
40
41         lidar::LidarDevice* getLidarDevice() {
42             return this->lidar_device_.get();
43         }
44
45         const bool isRunning() const {
46             return this->is_running_;
47         }
48
49         void initialize(std::shared_ptr<system::CarSystem> car_system);
50         void start();
51         void update();
52         void stop();
53         void terminate();
54
55     private:
56         std::shared_ptr<car::system::CarSystem> car_system;
57
58         bool is_initialized_ = false;
59         bool is_running_ = false;
60
61         std::unique_ptr<lidar::LidarDevice> lidar_device_;
62         std::unique_ptr<CameraDevice> camera_device_;
63     };
64 }
65 #endif

```

7.17 include/car/system/device/lidar/LidarDevice.h File Reference

```

#include <vector>
#include <rapidjson/document.h>
#include <RPLidar.h>

```

Classes

- class [car::system::device::lidar::LidarDevice](#)

Namespaces

- namespace [car](#)
- namespace [car::system](#)
- namespace [car::system::device](#)
- namespace [car::system::device::lidar](#)

7.18 LidarDevice.h

[Go to the documentation of this file.](#)

```

1 #ifndef LIDARDEVICE_H
2 #define LIDARDEVICE_H
3
4 #pragma once
5
6 #include <vector>
7
8 #include <rapidjson/document.h>
9
10 #include <RPLidar.h>
11
12 using namespace rplidar;
13
14 namespace car::system::device {
15     class DeviceManager;
16 }
17
18 namespace car::system::device::lidar
19 {
20     class LidarDevice
21     {
22     public:
23         std::vector<Measure> getScanData() const { return this->scan_data_; }
24
25         virtual void start() = 0;
26         virtual void update() = 0;
27         virtual void stop() = 0;
28
29         virtual void initialize() = 0;
30         virtual void terminate() = 0;
31         virtual void disconnect() = 0;
32
33     protected:
34         friend class DeviceManager;
35
36         void setScanData(const std::vector<Measure>& scan_data)
37         {
38             this->scan_data_ = scan_data;
39         }
40
41         std::vector<Measure> scan_data_;
42     };
43 }
44
45 #endif

```

7.19 include/car/system/device/lidar/LidarDummy.h File Reference

```

#include <fstream>
#include <spdlog/spdlog.h>
#include "LidarDevice.h"

```


Classes

- class [car::system::device::lidar::LidarDummy](#)

Namespaces

- namespace [car](#)
- namespace [car::system](#)
- namespace [car::system::device](#)
- namespace [car::system::device::lidar](#)

7.20 LidarDummy.h

[Go to the documentation of this file.](#)

```

1 #ifndef LIDARDUMMY_H
2 #define LIDARDUMMY_H
3
4 #pragma once
5
6 #include <fstream>
7 #include <spdlog/spdlog.h>
8
9 #include "LidarDevice.h"
10
11 namespace car::system::device::lidar
12 {
13     class LidarDummy final : public LidarDevice
14     {
15     public:
16         LidarDummy()
17         {
18             spdlog::warn("Currently using the LidarDummy");
19         };
20
21         void start() final override {};
22         void update() final override {};
23         void stop() final override {};
24         void initialize() final override {};
25         void terminate() final override {};
26         void disconnect() final override {};
27
28     private:
29     };
30 }
31
32 #endif

```

7.21 include/car/system/device/lidar/LidarScanner.h File Reference

```

#include "LidarDevice.h"
#include <memory>
#include <variant>
#include <RPLidar.h>
#include <tl/expected.hpp>
#include "car/configuration/Configuration.h"

```

Classes

- class [car::system::device::lidar::LidarScanner](#)

Namespaces

- namespace `car`
- namespace `car::system`
- namespace `car::system::device`
- namespace `car::system::device::lidar`

7.22 LidarScanner.h

[Go to the documentation of this file.](#)

```

1 #ifndef LIDARSCANNER_H
2 #define LIDARSCANNER_H
3
4 #pragma once
5
6 #include "LidarDevice.h"
7
8 #include <memory>
9 #include <variant>
10
11 #include <RPLidar.h>
12 #include <tl/expected.hpp>
13
14 #include "car/configuration/Configuration.h"
15
16 using namespace rplidar;
17
18 namespace car::system::device::lidar
19 {
20     class LidarScanner final : public LidarDevice
21     {
22     public:
23         [[nodiscard]] static tl::expected<std::unique_ptr<LidarScanner>, std::string>
24         create(std::shared_ptr<configuration::Configuration> configuration) noexcept
25         {
26             {
27                 auto maybe_lidar = RPLidar::create(configuration->lidar_port);
28                 if (maybe_lidar.has_value())
29                 {
30                     return std::make_unique<LidarScanner>(configuration, std::move(maybe_lidar.value()));
31                 }
32                 else
33                 {
34                     return tl::make_unexpected(maybe_lidar.error());
35                 }
36             }
37
38             // Do not call this constructor directly. Use the create method instead.
39             LidarScanner(std::shared_ptr<configuration::Configuration> configuration,
40                 std::unique_ptr<RPLidar> lidar) : configuration_(configuration), lidar_(std::move(lidar)) {}
41
42             void start() final override
43             {
44                 this->running = true;
45                 this->lidar_->start_motor();
46                 std::lock_guard<std::mutex> lock(this->scan_data_mutex_);
47                 this->scan_generator_ = this->lidar_->iter_scans();
48             };
49
50             void update() final override
51             {
52                 if (this->running) {
53                     std::lock_guard<std::mutex> lock(this->scan_data_mutex_);
54                     const auto& scan_generator =
55                         std::get<std::function<std::vector<Measure>()>>(this->scan_generator_);
56                     this->setScanData(scan_generator());
57                 }
58             };
59
60             void stop() final override
61             {
62                 if (this->running) {
63                     this->running = false;
64                     std::lock_guard<std::mutex> lock(this->scan_data_mutex_);
65                     this->scan_generator_ = nullptr;
66                     this->lidar_->stop();
67                     this->lidar_->stop_motor();
68                 }
69             }
70
71     private:
72         configuration::Configuration* configuration_ = nullptr;
73         RPLidar* lidar_ = nullptr;
74         std::mutex scan_data_mutex_;
75         std::function<std::vector<Measure>()> scan_generator_{};
76     };
77 }

```

```

66     }
67
68     void initialize() final override
69     {
70     };
71
72     void disconnect() final override
73     {
74         if (this->running) {
75             this->running = false;
76             std::lock_guard<std::mutex> lock(this->scan_data_mutex_);
77             this->scan_generator_ = nullptr;
78             this->lidar_->disconnect();
79         }
80     }
81
82     void terminate() final override
83     {
84         this->stop();
85         this->disconnect();
86     }
87
88 private:
89     std::atomic_bool running = false;
90
91     std::shared_ptr<configuration::Configuration> configuration_;
92
93     std::vector<Measure> scan_data_;
94
95     std::unique_ptr<RPLidar> lidar_;
96     std::variant<std::function<std::vector<Measure>()>, nullptr_t> scan_generator_ = nullptr;
97
98     std::mutex scan_data_mutex_;
99 };
100 }
101
102 #endif

```

7.23 include/car/system/logging/VectorSink.h File Reference

```

#include <algorithm>
#include <vector>
#include <fmt/format.h>
#include <spdlog/sinks/base_sink.h>
#include <spdlog/details/synchronous_factory.h>
#include <iostream>

```

Classes

- class [car::system::logging::VectorSink< Mutex >](#)

Namespaces

- namespace [car](#)
- namespace [car::system](#)
- namespace [car::system::logging](#)

Typedefs

- using [car::system::logging::vector_sink_mt](#) = [VectorSink< std::mutex >](#)

7.24 VectorSink.h

[Go to the documentation of this file.](#)

```

1  #ifndef VECTORSINK_CXX
2  #define VECTORSINK_CXX
3
4  #include <algorithm>
5  #include <vector>
6
7  #include <fmt/format.h>
8
9  #include <spdlog/sinks/base_sink.h>
10 #include <spdlog/details/synchronous_factory.h>
11 #include <iostream>
12
13 namespace car::system::logging
14 {
15     template <typename Mutex>
16     class VectorSink : public spdlog::sinks::base_sink<Mutex>
17     {
18     public:
19         VectorSink(int max_lines) : max_lines(max_lines)
20         {
21         }
22
23         void sink_it_(const spdlog::details::log_msg &msg) override
24         {
25             spdlog::memory_buf_t formatted;
26             spdlog::sinks::base_sink<Mutex>::formatter->format(msg, formatted);
27             if (this->log_messages.size() < this->max_lines)
28             {
29                 this->log_messages.push_back(std::string(formatted.data(), formatted.size()));
30             }
31             else
32             {
33                 std::rotate(this->log_messages.begin(), this->log_messages.begin() + 1,
34                             this->log_messages.end());
35                 this->log_messages[this->log_messages.size() - 1] = std::string(formatted.data(),
36                                         formatted.size());
37             }
38         };
39
40         void flush_() override
41         {
42             this->log_messages.clear();
43         };
44
45         const std::vector<std::string> &get_log_messages() const
46         {
47             return this->log_messages;
48         }
49
50     private:
51         const int max_lines;
52
53         std::vector<std::string> log_messages;
54     };
55     using vector_sink_mt = VectorSink<std::mutex>;
56 }
57 #endif

```

7.25 include/car/system/messaging/MessagingSystem.h File Reference

```

#include <functional>
#include <memory>
#include <ixwebsocket/IXNetSystem.h>
#include <ixwebsocket/IXWebSocket.h>
#include <nod/nod.hpp>
#include <rapidjson/rapidjson.h>
#include <rapidjson/document.h>
#include "utils/Utility.hpp"
#include "car/configuration/Configuration.h"

```

Classes

- class `car::system::messaging::MessagingSystem`
- struct `car::system::messaging::MessagingSystem::FirstMessageStruct`

Namespaces

- namespace `car`
- namespace `car::system`
- namespace `car::system::messaging`

7.26 MessagingSystem.h

[Go to the documentation of this file.](#)

```

1 #ifndef MESSAGINGSYSTEM_H
2 #define MESSAGINGSYSTEM_H
3
4 #pragma once
5
6 #include <functional>
7 #include <memory>
8
9 #include <ixwebsocket/IXNetSystem.h>
10 #include <ixwebsocket/IXWebSocket.h>
11
12 #include <nod/nod.hpp>
13
14 #include <rapidjson/rapidjson.h>
15 #include <rapidjson/document.h>
16
17 #include "utils/Utility.hpp"
18
19 #include "car/configuration/Configuration.h"
20
21 namespace car::system::messaging
22 {
23     class MessagingSystem
24     {
25     public:
26         MessagingSystem();
27
28         void initialize(std::shared_ptr<configuration::Configuration> configuration);
29         void initializeWebSocket();
30         const tl::expected<nullptr_t, std::string> tryConnect();
31         void stop();
32         void terminate();
33
34         // Necessary for the reloading the configuration
35         void setConfiguration(std::shared_ptr<configuration::Configuration> configuration);
36
37         nod::signal<void(const std::string, const rapidjson::Document*)>& getCommandSignal() { return
this->command_signal_; }
38         nod::signal<void(const std::string, const rapidjson::Document*)>& getSelectionSignal() { return
this->selection_signal_; }
39         nod::signal<void(const std::string)>& getMessageSignal() { return this->message_signal_; }
40         nod::signal<void(const std::string)>& getDisconnectSignal() { return this->on_disconnect_signal_;
}
41
42         void onMessageCallback(const ix::WebSocketMessagePtr& msg) const;
43         void onDisconnect(const std::string);
44
45         const std::string getUUID() const { return this->uuid_; }
46         void handleMessage(const std::string& message) const;
47         void sendMessage(const std::string& message);
48
49         struct FirstMessageStruct
50         {
51             std::string error_message;
52             std::string uuid;
53             std::condition_variable condition;
54         };
55         void onFirstMessage(const ix::WebSocketMessagePtr& msg, FirstMessageStruct&
first_message_struct);
56

```

```

57         const bool isConnected() const { return this->connected_; }
58
59         nod::signal<void(std::string)> on_disconnect_signal_;
60
61         nod::signal<void(const std::string)> message_signal_;
62         nod::signal<void(const std::string, const rapidjson::Document&)> command_signal_;
63         nod::signal<void(const std::string, const rapidjson::Document&)> selection_signal_;
64
65     private:
66         tl::expected<std::string, std::string> getFirstMessage();
67
68         std::shared_ptr<configuration::Configuration> configuration_;
69
70         std::unique_ptr<ix::WebSocket> websocket_;
71         std::string websocket_url_;
72
73         std::string uuid_;
74
75         bool connected_ = false;
76     };
77 };
78
79 #endif

```

7.27 include/car/system/messaging/StreamType.h File Reference

Enumerations

- enum [StreamType](#) { [None](#) = 0 , [Lidar](#) , [Camera](#) , [Both](#) }

7.27.1 Enumeration Type Documentation

7.27.1.1 StreamType

enum [StreamType](#)

Enumerator

None	
Lidar	
Camera	
Both	

7.28 StreamType.h

[Go to the documentation of this file.](#)

```

1 #ifndef STREAM_TYPE_H
2 #define STREAM_TYPE_H
3
4 #pragma once
5
6 enum StreamType {
7     None = 0,
8     Lidar,
9     Camera,

```

```

10     Both,
11 };
12
13 #endif

```

7.29 include/car/system/movement/controller/AbstractMovementController.h File Reference

Classes

- class [car::system::movement::controller::AbstractMovementController](#)

Namespaces

- namespace [car](#)
- namespace [car::system](#)
- namespace [car::system::movement](#)
- namespace [car::system::movement::controller](#)

7.30 AbstractMovementController.h

[Go to the documentation of this file.](#)

```

1 #ifndef ABSTRACTWHEELCONTROLLER_H
2 #define ABSTRACTWHEELCONTROLLER_H
3
4 #pragma once
5
6 namespace car::system::movement::controller
7 {
8     class AbstractMovementController
9     {
10     public:
11         virtual void initialize() = 0;
12         virtual void stop() = 0;
13         virtual void terminate() = 0;
14
15         virtual void setRearWheelsSpeed(const int speed) = 0;
16
17         virtual void setRearLeftWheelSpeed(const int speed) = 0;
18         virtual void setRearRightWheelSpeed(const int speed) = 0;
19
20         virtual void setFrontWheelsAngle(const float angle) = 0;
21         virtual void setCameraServo1Angle(const float angle) = 0;
22         virtual void setCameraServo2Angle(const float angle) = 0;
23
24         virtual void setRearWheelsDirectionToForward() = 0;
25         virtual void setRearLeftWheelDirectionToForward() = 0;
26         virtual void setRearRightWheelDirectionToForward() = 0;
27
28         virtual void setRearWheelsDirectionToBackward() = 0;
29         virtual void setRearLeftWheelDirectionToBackward() = 0;
30         virtual void setRearRightWheelDirectionToBackward() = 0;
31     };
32 } // namespace car::system::movement::controller
33
34 #endif

```

7.31 include/car/system/movement/controller/DeviceMovementController.h File Reference

7.32 DeviceMovementController.h

[Go to the documentation of this file.](#)

```

1 #ifndef __linux__
2 #ifndef DEVICEMOVEMENTCONTROLLER_H
3 #define DEVICEMOVEMENTCONTROLLER_H
4
5 #pragma once
6
7 #include <memory>
8
9 #include "AbstractMovementController.h"
10
11 #include "car/system/movement/devices/Servo.h"
12 #include "car/system/movement/devices/RearWheel.h"
13
14 using namespace car::system::movement::devices;
15
16 namespace car::system::movement::controller
17 {
18     static constexpr int Motor_A = 17;
19     static constexpr int Motor_B = 27;
20     static constexpr int PWM_A = 4;
21     static constexpr int PWM_B = 5;
22
23     static constexpr int MIN_PULSE_WIDTH = 900;
24     static constexpr int MAX_PULSE_WIDTH = 2100;
25     static constexpr int FREQUENCY = 50;
26
27     static constexpr int BUS_NUMBER = 1;
28
29     class DeviceMovementController : public AbstractMovementController
30     {
31     public:
32         [[nodiscard]] DeviceMovementController();
33
34         void initialize() final override;
35
36         void stop() final override;
37
38         void terminate() final override;
39
40         void setRearWheelsSpeed(const int speed) final override;
41
42         void setRearLeftWheelSpeed(const int speed) final override;
43
44         void setRearRightWheelSpeed(const int speed) final override;
45
46         void setFrontWheelsAngle(const float angle) final override;
47
48         void setCameraServo1Angle(const float angle) final override;
49
50         void setCameraServo2Angle(const float angle) final override;
51
52         void setRearWheelsDirectionToForward() final override;
53
54         void setRearLeftWheelDirectionToForward() final override;
55
56         void setRearRightWheelDirectionToForward() final override;
57
58         void setRearWheelsDirectionToBackward() final override;
59
60         void setRearLeftWheelDirectionToBackward() final override;
61
62         void setRearRightWheelDirectionToBackward() final override;
63
64     private:
65         std::shared_ptr<PCA9685> pwm;
66
67         std::unique_ptr<Servo> front_wheels_;
68         std::unique_ptr<Servo> camera_servo_1_;
69         std::unique_ptr<Servo> camera_servo_2_;
70
71         std::unique_ptr<RearWheel> rear_left_wheel_;
72         std::unique_ptr<RearWheel> rear_right_wheel_;
73     };
74 } // namespace car::system::movement::controller
75

```



```

76 #endif
77 #endif // __linux__

```

7.33 include/car/system/movement/controller/DummyMovementController.h File Reference

```
#include "AbstractMovementController.h"
```

Classes

- class [car::system::movement::controller::DummyMovementController](#)

Namespaces

- namespace [car](#)
- namespace [car::system](#)
- namespace [car::system::movement](#)
- namespace [car::system::movement::controller](#)

7.34 DummyMovementController.h

[Go to the documentation of this file.](#)

```

1 #ifndef DUMMYWHEELCONTROLLER_H
2 #define DUMMYWHEELCONTROLLER_H
3
4 #pragma once
5
6 #include "AbstractMovementController.h"
7
8 namespace car::system::movement::controller
9 {
10     class DummyMovementController : public AbstractMovementController
11     {
12     public:
13         void initialize() final override {};
14
15         void stop() final override;
16
17         void terminate() final override {};
18
19         void setRearWheelsSpeed(const int speed) final override;
20
21         void setRearLeftWheelSpeed(const int speed) final override;
22
23         void setRearRightWheelSpeed(const int speed) final override;
24
25         void setFrontWheelsAngle(const float angle) final override;
26
27         void setCameraServo1Angle(const float angle) final override;
28
29         void setCameraServo2Angle(const float angle) final override;
30
31         void setRearWheelsDirectionToForward() final override;
32
33         void setRearLeftWheelDirectionToForward() final override;
34
35         void setRearRightWheelDirectionToForward() final override;
36
37         void setRearWheelsDirectionToBackward() final override;
38
39         void setRearLeftWheelDirectionToBackward() final override;
40
41         void setRearRightWheelDirectionToBackward() final override;
42
43     private:
44     };
45 } // namespace car::system::movement::controller
46
47 #endif

```

7.35 include/car/system/movement/devices/RearWheel.h File Reference

7.36 RearWheel.h

[Go to the documentation of this file.](#)

```

1 #ifndef __linux__
2 #ifndef REARWHEEL_H
3 #define REARWHEEL_H
4
5 #include <memory>
6
7 #include <PCA9685.h>
8 #include <TB6612.h>
9
10 // Made with the help of ChatGPT
11
12 namespace car::system::movement::devices
13 {
14     class RearWheel
15     {
16     public:
17         RearWheel(std::shared_ptr<PCA9685> pwm, std::unique_ptr<TB6612> motor);
18
19         void forward();
20
21         void backward();
22
23         void stop();
24
25         int getSpeed() const;
26
27         void setSpeed(const int speed);
28
29         void ready();
30
31     private:
32         std::shared_ptr<PCA9685> pwm_;
33         std::unique_ptr<TB6612> motor_;
34
35         int speed_;
36     };
37 } // namespace car::system::movement::wheels
38
39 #endif
40 #endif

```

7.37 include/car/system/movement/devices/Servo.h File Reference

7.38 Servo.h

[Go to the documentation of this file.](#)

```

1 #ifndef __linux__
2 #ifndef SERVO_H
3 #define SERVO_H
4
5 #include <algorithm>
6 #include <memory>
7
8 #include <PCA9685.h>
9
10 namespace car::system::movement::devices
11 {
12     class Servo
13     {
14     private:
15         static int map(int x, int in_min, int in_max, int out_min, int out_max)
16         {
17             return ((x - in_min) * (out_max - out_min) / (in_max - in_min) + out_min);
18         }
19
20         static constexpr int MIN_PULSE_WIDTH = 900;
21         static constexpr int MAX_PULSE_WIDTH = 2100;
22         static constexpr int FREQUENCY = 50;
23
24     };
25 }
26

```

```

27
28     public:
29         Servo(std::shared_ptr<PCA9685> pwm, int channel);
30
31         // Some of the code was from: https://github.com/chaoticmachinery/pca9685
32         int getAnalogAngle() const;
33
34         int getAngle() const;
35
36         // Some of the code was from: https://github.com/chaoticmachinery/pca9685
37         void setAngle(const int angle);
38
39         void reset();
40
41     private:
42         const std::shared_ptr<PCA9685> pwm_;
43         const int channel_;
44
45         int angle_;
46     };
47 } // namespace car::system::movement::wheels
48
49 #endif
50 #endif // __linux__

```

7.39 include/car/system/movement/MovementSystem.h File Reference

```

#include <memory>
#include "car/system/movement/controller/AbstractMovementController.h"

```

Classes

- class `car::system::movement::MovementSystem`

Namespaces

- namespace `car`
- namespace `car::system`
- namespace `car::system::movement`

7.40 MovementSystem.h

[Go to the documentation of this file.](#)

```

1 #ifndef MOVEMENTSYSTEM_H
2 #define MOVEMENTSYSTEM_H
3
4 #pragma once
5
6 #include <memory>
7
8 #include "car/system/movement/controller/AbstractMovementController.h"
9
10 using namespace car::system::movement::controller;
11
12 namespace car::system::movement
13 {
14     class MovementSystem
15     {
16     public:
17         MovementSystem(std::unique_ptr<AbstractMovementController> movement_controller) :
18             movement_controller(std::move(movement_controller)) {}
19
20         void initialize()
21         {

```

```

21         this->movement_controller->initialize();
22     }
23
24     void start()
25     {
26     }
27
28     void stop()
29     {
30         this->movement_controller->stop();
31     }
32
33     void terminate()
34     {
35         this->movement_controller->terminate();
36     }
37
38 #pragma region Wheels
39 void setRearWheelsSpeed(const int speed) const
40 {
41     this->movement_controller->setRearWheelsSpeed(speed);
42 }
43
44 void setRearLeftWheelSpeed(const int speed) const
45 {
46     this->movement_controller->setRearLeftWheelSpeed(speed);
47 }
48
49 void setRearRightWheelSpeed(const int speed) const
50 {
51     this->movement_controller->setRearRightWheelSpeed(speed);
52 }
53
54 void setFrontWheelsAngle(const float angle) const
55 {
56     this->movement_controller->setFrontWheelsAngle(angle);
57 }
58
59 void setCameraServo1Angle(const float angle) const
60 {
61     this->movement_controller->setCameraServo1Angle(angle);
62 }
63
64 void setCameraServo2Angle(const float angle) const
65 {
66     this->movement_controller->setCameraServo2Angle(angle);
67 }
68
69 void setRearWheelsDirectionToForward() const
70 {
71     this->movement_controller->setRearWheelsDirectionToForward();
72 }
73
74 void setRearLeftWheelDirectionToForward() const
75 {
76     this->movement_controller->setRearLeftWheelDirectionToForward();
77 }
78
79 void setRearRightWheelDirectionToForward() const
80 {
81     this->movement_controller->setRearRightWheelDirectionToForward();
82 }
83
84 void setRearWheelsDirectionToBackward() const
85 {
86     this->movement_controller->setRearWheelsDirectionToBackward();
87 }
88
89 void setRearLeftWheelDirectionToBackward() const
90 {
91     this->movement_controller->setRearLeftWheelDirectionToBackward();
92 }
93
94 void setRearRightWheelDirectionToBackward() const
95 {
96     this->movement_controller->setRearRightWheelDirectionToBackward();
97 }
98 #pragma endregion
99
100     ~MovementSystem() {};
101
102     private:
103         std::unique_ptr<AbstractMovementController> movement_controller;
104     };
105 };
106
107 #endif

```

7.41 src/car/system/CarSystem.cpp File Reference

```
#include "car/system/CarSystem.h"
#include <memory>
#include <rapidjson/rapidjson.h>
#include <rapidjson/document.h>
#include <rapidjson/stringbuffer.h>
#include <rapidjson/writer.h>
#include <tobiaslocker_base64/base64.hpp>
#include "car/configuration/Configuration.h"
#include "car/system/device/DeviceManager.h"
#include "car/system/device/lidar/LidarDevice.h"
#include "car/system/device/CameraDevice.h"
#include "car/system/messaging/MessagingSystem.h"
#include "car/system/movement/MovementSystem.h"
#include "car/plugin/PluginManager.h"
```

Namespaces

- namespace [car](#)
- namespace [car::system](#)

7.42 src/car/system/device/CameraDevice.cpp File Reference

```
#include "car/system/device/CameraDevice.h"
```

Namespaces

- namespace [car](#)
- namespace [car::system](#)
- namespace [car::system::device](#)

7.43 src/car/system/device/DeviceManager.cpp File Reference

```
#include "car/system/device/DeviceManager.h"
#include "car/system/CarSystem.h"
```

Namespaces

- namespace [car](#)
- namespace [car::system](#)
- namespace [car::system::device](#)

7.44 src/car/system/messaging/MessagingSystem.cpp File Reference

```
#include "car/system/messaging/MessagingSystem.h"
#include <functional>
#include <memory>
#include <ixwebsocket/IXNetSystem.h>
#include <ixwebsocket/IXWebSocket.h>
#include <nod/nod.hpp>
#include <spdlog/spdlog.h>
#include <rapidjson/rapidjson.h>
#include <rapidjson/document.h>
#include <fmt/format.h>
#include "car/configuration/Configuration.h"
```

Namespaces

- namespace [car](#)
- namespace [car::system](#)
- namespace [car::system::messaging](#)

7.45 src/car/system/movement/controller/DeviceMovementController.cpp File Reference

7.46 src/car/system/movement/controller/DummyMovementController.cpp File Reference

```
#include "car/system/movement/controller/DummyMovementController.h"
#include <spdlog/spdlog.h>
```

Namespaces

- namespace [car](#)
- namespace [car::system](#)
- namespace [car::system::movement](#)
- namespace [car::system::movement::controller](#)

7.47 src/car/system/movement/devices/RearWheel.cpp File Reference

7.48 src/car/system/movement/devices/Servo.cpp File Reference

7.49 tests/pca9685/test_front_wheels.cpp File Reference

```
#include "PCA9685.h"
#include <iostream>
#include <algorithm>
#include <thread>
```

Functions

- int [setAngle](#) (int &angle, PCA9685 pwm, int channel)
- int [map](#) (int x, int in_min, int in_max, int out_min, int out_max)
- int [setAngleToAnalog](#) (int angle)
- int [main](#) ()

Variables

- int [offset](#) = 0

7.49.1 Function Documentation

7.49.1.1 main()

```
int main ( )
```

7.49.1.2 map()

```
int map (
    int x,
    int in_min,
    int in_max,
    int out_min,
    int out_max )
```

Following method clamps the x to in_min and in_max. Afterwards, it puts the result of that into the range of out_min and out_max

7.49.1.3 setAngle()

```
int setAngle (
    int & angle,
    PCA9685 pwm,
    int channel )
```

7.49.1.4 setAngleToAnalog()

```
int setAngleToAnalog (
    int angle )
```

7.49.2 Variable Documentation

7.49.2.1 offset

```
int offset = 0
```

7.50 tests/tb6612/test_rear_wheels.cpp File Reference

```
#include <pigpio.h>
#include <iostream>
#include <memory>
#include <thread>
#include <chrono>
#include <algorithm>
#include "PCA9685.h"
#include "TB6612.h"
```

Classes

- class [BackWheels](#)

Functions

- void [test](#) ()
- int [main](#) ()

7.50.1 Function Documentation

7.50.1.1 main()

```
int main ( )
```

7.50.1.2 test()

```
void test ( )
```


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