

## Behaviour Tree PiCar-V

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# Chapter 1

## Behaviour Tree PiCar Daemon

### 1.1 Installation:

Run the follow commands to install the Daemon:

```
sudo chmod +x ./install_script.sh # Grant permission to install_script to run as exe
systemctl stop rpi_daemon # Stop any previous rpi_daemon
sudo ./install_script.sh install # Install the Daemon
sudo systemctl daemon-reload # Reload the Daemon if there was any previous
sudo systemctl start rpi_daemon # Start the new Daemon
```

Or use the single command:

```
sudo chmod +x ./install_script.sh && systemctl stop rpi_daemon && sudo ./install_script.sh install && sudo
systemctl daemon-reload && sudo systemctl start rpi_daemon
```

### 1.2 View Logs

```
systemctl status rpi_daemon.service journalctl -u rpi\_daemon
```



## Chapter 2

# Raspberry Pi Daemon

This will only work for Linux.

### 2.1 Install Raspberry Pi Daemon

```
xmake install --admin rpi_daemon
```

### 2.2 Enable / Disable Daemon to run on startup

```
sudo systemctl [enable|disable] rpi_daemon
```

### 2.3 Start / Stop / Restart Daemon

```
sudo systemctl [start/stop/restart] rpi_daemon
```

### 2.4 View Logs

```
systemctl status rpi_daemon.service journalctl -u rpi_daemon
```

### 2.5 Clear Past Logs

```
sudo journalctl -m --vacuum-time=1s
```

### 2.6 Reload Daemon

```
sudo systemctl reload rpi_daemon
```

## 2.7 Change Config

```
sudo nano /etc/rpi_daemon/rpi_daemon.conf
```

## 2.8 Uninstall Raspberry Pi Daemon

```
xmake uninstall --admin rpi_daemon
```

## 2.9 Speedrun

```
sudo systemctl stop rpi_daemon && xmake && xmake install --admin rpi_daemon  
&& sudo systemctl daemon-reload && sudo systemctl start rpi_daemon
```



## Chapter 3

# Raspberry Pi

This sub-project contains three other sub-projects:

- common - Main functionality is stored here
- daemon - Daemon Application for seamless startup and termination
- tui - Terminal User Interface

### 3.1 Main Technologies

- C++17
- `ixwebsocket`
- `ftxui`
- `rapidjson`

### 3.2 Setting up Raspberry Pi

If you want to setup the raspberry pi, you can go to [SETUP.md](#)



## Chapter 4

# Behaviour Tree PiCar-V Setup

Set up the following first:

- Wifi - Use the Mobile Hotspot feature of your device
- SSH - Enable
- I2C - Enable

See if Wifi does not connect: [Raspberrypi Stackexchange](#)

Now connect to the Raspberry Pi with SSH

Run the following commands to get the raspberry pi running:

```
sudo apt-get install build-essential
curl -fsSL https://xmake.io/shget.text | bash
source ~/.xmake/profile
```

Run the following commands before cross compilation:

```
sudo apt update
sudo apt upgrade
sudo apt dist-upgrade
```

or `sudo apt update && sudo apt upgrade && sudo apt dist-upgrade`



## Chapter 5

# Raspberry Pi

This sub-project handles all the logic of the Sunfounder PiCar.

The system is broken down to 3 sub systems:

- lidar - Handles the lidar scanner of the Raspberry Pi
- messaging - Handles the websocket of the Raspberry Pi
- movement - Handles the movement of the Sunfounder PiCar

The system is then displayed by the `CarConsole`.

### 5.1 Installation

Run the following command to build the sub-project:

```
xmake build raspberry_pi
```

To connect the Raspberry Pi to the backend, you would need the `IPv4 Address` of your Computer/Server and change the host to the value in `IPv4 Address`.

If this doesn't work, you may need to restart your Computer/Server.

### 5.2 Main Technologies

- C++17
- `ixwebsocket`
- `ftxui`
- `nlohmann_json`

### 5.3 Setting up Raspberry Pi

If you want to setup the raspberry pi, you can go to [SETUP.md](#)



## Chapter 6

# Namespace Index

### 6.1 Namespace List

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## Chapter 7

# Hierarchical Index

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# Class Index

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## Chapter 10

# Namespace Documentation

### 10.1 behaviour\_tree Namespace Reference

#### Classes

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

### 10.2 car Namespace Reference

#### Namespaces

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

### 10.3 car::configuration Namespace Reference

#### Classes

- struct [Configuration](#)
- class [JsonConfiguration](#)

### 10.4 car::display Namespace Reference

#### Namespaces

- namespace [console](#)

## 10.5 car::display::console Namespace Reference

### Namespaces

- namespace [component](#)
- namespace [screen](#)

### Classes

- class [CarConsole](#)

## 10.6 car::display::console::component Namespace Reference

### Namespaces

- namespace [debug](#)
- namespace [main](#)
- namespace [settings](#)

## 10.7 car::display::console::component::debug Namespace Reference

### Classes

- class [DebugEnabler](#)
- class [DebugLidarCheckbox](#)
- class [DebugMessagingTextbox](#)
- class [DebugMovementRenderer](#)

## 10.8 car::display::console::component::main Namespace Reference

### Classes

- class [ConnectButton](#)
- class [MainErrorModal](#)
- class [MainExitModal](#)

## 10.9 car::display::console::component::settings Namespace Reference

### Classes

- class [SettingsEditConfig](#)



## 10.10 car::display::console::screen Namespace Reference

### Classes

- class [LoggingScreen](#)
- class [MainScreen](#)
- class [SettingsScreen](#)

## 10.11 car::plugin Namespace Reference

### Classes

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

## 10.12 car::system Namespace Reference

### Namespaces

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

### Classes

- class [CarSystem](#)

## 10.13 car::system::device Namespace Reference

### Namespaces

- namespace [lidar](#)

### Classes

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

## 10.14 car::system::device::lidar Namespace Reference

### Classes

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

## 10.15 car::system::logging Namespace Reference

### Classes

- class [VectorSink](#)

### Typedefs

- using [vector\\_sink\\_mt](#) = [VectorSink](#)< std::mutex >

### 10.15.1 Typedef Documentation

#### 10.15.1.1 vector\_sink\_mt

using [car::system::logging::vector\\_sink\\_mt](#) = typedef [VectorSink](#)<std::mutex>

## 10.16 car::system::messaging Namespace Reference

### Classes

- class [MessagingSystem](#)

## 10.17 car::system::movement Namespace Reference

### Namespaces

- namespace [controller](#)

### Classes

- class [MovementSystem](#)

## 10.18 car::system::movement::controller Namespace Reference

### Classes

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

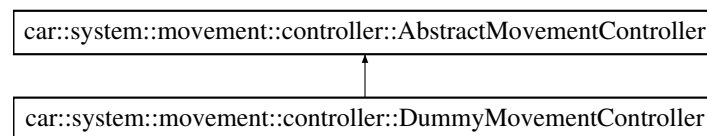
## Chapter 11

# Class Documentation

### 11.1 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

#### 11.1.1 Member Function Documentation

#### 11.1.1.1 initialize()

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

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

#### 11.1.1.2 setCameraServo1Angle()

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

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

#### 11.1.1.3 setCameraServo2Angle()

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

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

#### 11.1.1.4 setFrontWheelsAngle()

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

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

#### 11.1.1.5 setRearLeftWheelDirectionToBackward()

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

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

#### 11.1.1.6 setRearLeftWheelDirectionToForward()

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

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

#### 11.1.1.7 setRearLeftWheelSpeed()

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

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

#### 11.1.1.8 setRearRightWheelDirectionToBackward()

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

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

#### 11.1.1.9 setRearRightWheelDirectionToForward()

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

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

#### 11.1.1.10 setRearRightWheelSpeed()

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

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

#### 11.1.1.11 `setRearWheelsDirectionToBackward()`

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

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

#### 11.1.1.12 `setRearWheelsDirectionToForward()`

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

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

#### 11.1.1.13 `setRearWheelsSpeed()`

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

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

#### 11.1.1.14 `stop()`

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

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

#### 11.1.1.15 `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:

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

## 11.2 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](#)

## 11.2.1 Constructor & Destructor Documentation

### 11.2.1.1 BackWheels()

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

## 11.2.2 Member Function Documentation

### 11.2.2.1 backward()

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

#### 11.2.2.2 calibration()

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

#### 11.2.2.3 caliLeft()

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

#### 11.2.2.4 caliOK()

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

#### 11.2.2.5 caliRight()

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

#### 11.2.2.6 forward()

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

#### 11.2.2.7 getSpeed()

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

#### 11.2.2.8 ready()

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

#### 11.2.2.9 setSpeed()

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



### 11.2.2.10 stop()

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

## 11.2.3 Member Data Documentation

### 11.2.3.1 cali\_forward\_A

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

### 11.2.3.2 cali\_forward\_B

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

### 11.2.3.3 forward\_A

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

### 11.2.3.4 forward\_B

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

### 11.2.3.5 left\_wheel

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

### 11.2.3.6 pca9685

```
PCA9685 BackWheels::pca9685
```

### 11.2.3.7 right\_wheel

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

### 11.2.3.8 speed

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

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

- [common/tests/tb6612/test\\_rear\\_wheels.cpp](#)

## 11.3 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](#)

## 11.3.1 Member Function Documentation

### 11.3.1.1 `_setBehaviourTree()`

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

### 11.3.1.2 `getName()`

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

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

### 11.3.1.3 `handleCommand()`

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

### 11.3.1.4 `initialize()`

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

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

### 11.3.1.5 `setBehaviourTree()`

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

#### 11.3.1.6 startBehaviourTree()

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

#### 11.3.1.7 stop()

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

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

#### 11.3.1.8 stopBehaviourTree()

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

#### 11.3.1.9 update()

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

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

### 11.3.2 Member Data Documentation

#### 11.3.2.1 behaviour\_tree

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

#### 11.3.2.2 car\_system

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

### 11.3.2.3 context

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

### 11.3.2.4 last\_connected

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

### 11.3.2.5 tick\_count

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

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

- common/include/behaviour\_tree/[BehaviourTreeHandler.hpp](#)

## 11.4 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](#)

## 11.4.1 Constructor & Destructor Documentation

### 11.4.1.1 CameraDevice() [1/3]

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

### 11.4.1.2 CameraDevice() [2/3]

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

### 11.4.1.3 CameraDevice() [3/3]

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

### 11.4.1.4 ~CameraDevice()

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

## 11.4.2 Member Function Documentation

#### 11.4.2.1 create()

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

#### 11.4.2.2 disconnect()

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

#### 11.4.2.3 getFrameBuffer()

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

#### 11.4.2.4 operator=() [1/2]

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

#### 11.4.2.5 operator=() [2/2]

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

#### 11.4.2.6 start()

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

#### 11.4.2.7 stop()

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

#### 11.4.2.8 terminate()

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

#### 11.4.2.9 update()

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

### 11.4.3 Friends And Related Function Documentation

#### 11.4.3.1 DeviceManager

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

### 11.4.4 Member Data Documentation

#### 11.4.4.1 camera\_

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

#### 11.4.4.2 camera\_mutex\_

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

#### 11.4.4.3 configuration

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



#### 11.4.4.4 connected\_

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

#### 11.4.4.5 frame\_buffer\_

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

#### 11.4.4.6 last

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

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

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

## 11.5 car::display::console::CarConsole Class Reference

```
#include <CarConsole.h>
```

### Public Member Functions

- [CarConsole](#) (std::shared\_ptr< [CarSystem](#) > car\_system, std::shared\_ptr< [JsonConfiguration](#) > json\_configuration, std::shared\_ptr< [logging::vector\\_sink\\_mt](#) > vector\_sink)
- void [initialize](#) ()
- void [run](#) ()
- void [terminate](#) ()

### Private Attributes

- std::shared\_ptr< [CarSystem](#) > car\_system
- std::shared\_ptr< [JsonConfiguration](#) > json\_configuration
- std::shared\_ptr< [logging::vector\\_sink\\_mt](#) > vector\_sink

### 11.5.1 Constructor & Destructor Documentation

#### 11.5.1.1 CarConsole()

```
car::display::console::CarConsole::CarConsole (
    std::shared_ptr< CarSystem > car_system,
    std::shared_ptr< JsonConfiguration > json_configuration,
    std::shared_ptr< logging::vector_sink_mt > vector_sink )
```

### 11.5.2 Member Function Documentation

#### 11.5.2.1 initialize()

```
void car::display::console::CarConsole::initialize ( )
```

#### 11.5.2.2 run()

```
void car::display::console::CarConsole::run ( )
```

#### 11.5.2.3 terminate()

```
void car::display::console::CarConsole::terminate ( )
```

### 11.5.3 Member Data Documentation

#### 11.5.3.1 car\_system

```
std::shared_ptr<CarSystem> car::display::console::CarConsole::car_system [private]
```

#### 11.5.3.2 json\_configuration

```
std::shared_ptr<JsonConfiguration> car::display::console::CarConsole::json_configuration
[private]
```

### 11.5.3.3 vector\_sink

```
std::shared_ptr<logging::vector_sink_mt> car::display::console::CarConsole::vector_sink [private]
```

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

- [tui/src/car/display/console/CarConsole.h](#)
- [tui/src/car/display/console/CarConsole.cpp](#)

## 11.6 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](#)

### 11.6.1 Constructor & Destructor Documentation

#### 11.6.1.1 CarContext()

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

### 11.6.2 Member Function Documentation

### 11.6.2.1 \_()

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

### 11.6.2.2 getCarSystem()

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

## 11.6.3 Member Data Documentation

### 11.6.3.1 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:

- common/include/behaviour\_tree/[CarContext.hpp](#)

## 11.7 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

## 11.7.1 Constructor & Destructor Documentation

### 11.7.1.1 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 )
```

## 11.7.2 Member Function Documentation

### 11.7.2.1 disconnect()

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

### 11.7.2.2 getConfiguration()

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

### 11.7.2.3 getDeviceManager()

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

### 11.7.2.4 getMessagingSystem()

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

### 11.7.2.5 getMovementSystem()

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

### 11.7.2.6 getPlugin()

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

### 11.7.2.7 initialize()

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

### 11.7.2.8 reload()

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

### 11.7.2.9 sendData()

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

#### 11.7.2.10 setConfiguration()

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

#### 11.7.2.11 start()

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

#### 11.7.2.12 stop()

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

#### 11.7.2.13 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.

#### 11.7.2.14 tryConnect()

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

#### 11.7.2.15 update()

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

### 11.7.3 Member Data Documentation

#### 11.7.3.1 configuration\_

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

### 11.7.3.2 device\_manager\_

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

### 11.7.3.3 initialized

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

### 11.7.3.4 messaging\_system\_

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

### 11.7.3.5 movement\_system\_

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

### 11.7.3.6 plugin\_manager\_

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

### 11.7.3.7 started

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

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

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

## 11.8 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

### 11.8.1 Member Function Documentation

#### 11.8.1.1 [getCameraFpsInterval\(\)](#)

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

#### 11.8.1.2 [setCameraFps\(\)](#)

```
void car::configuration::Configuration::setCameraFps (
    const int camera_fps ) [inline]
```

### 11.8.2 Member Data Documentation

#### 11.8.2.1 [behaviour\\_tree\\_update\\_ms\\_interval](#)

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

### 11.8.2.2 camera\_fps

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

### 11.8.2.3 camera\_fps\_interval

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

### 11.8.2.4 camera\_index

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

### 11.8.2.5 host

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

### 11.8.2.6 lidar\_port

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

### 11.8.2.7 use\_camera

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

### 11.8.2.8 use\_lidar

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

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

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

## 11.9 car::display::console::component::main::ConnectButton Class Reference

### Public Member Functions

- [ConnectButton](#) (std::shared\_ptr< [CarSystem](#) > *car\_system*, Box &box)
- Component [element](#) ()

### Public Attributes

- std::function< void(std::string)> [on\\_connect\\_failure](#) = [] (std::string \_) {}

### Private Attributes

- std::shared\_ptr< [CarSystem](#) > *car\_system*
- bool [main\\_debounce](#) = false
- bool [button\\_pressed](#) = false
- std::string [main\\_button\\_text](#) = "Start Car Application"
- Component [main\\_button](#)

### 11.9.1 Constructor & Destructor Documentation

#### 11.9.1.1 ConnectButton()

```
car::display::console::component::main::ConnectButton::ConnectButton (
    std::shared_ptr< CarSystem > car_system,
    Box & box ) [inline]
```

### 11.9.2 Member Function Documentation

#### 11.9.2.1 element()

```
Component car::display::console::component::main::ConnectButton::element ( ) [inline]
```

### 11.9.3 Member Data Documentation

### 11.9.3.1 button\_pressed

```
bool car::display::console::component::main::ConnectButton::button_pressed = false [private]
```

### 11.9.3.2 car\_system

```
std::shared_ptr<CarSystem> car::display::console::component::main::ConnectButton::car_system  
[private]
```

### 11.9.3.3 main\_button

```
Component car::display::console::component::main::ConnectButton::main_button [private]
```

### 11.9.3.4 main\_button\_text

```
std::string car::display::console::component::main::ConnectButton::main_button_text = "Start  
Car Application" [private]
```

### 11.9.3.5 main\_debounce

```
bool car::display::console::component::main::ConnectButton::main_debounce = false [private]
```

### 11.9.3.6 on\_connect\_failure

```
std::function<void(std::string)> car::display::console::component::main::ConnectButton::on_↵  
connect_failure = [] (std::string _) {}
```

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

- tui/src/car/display/console/component/main/[ConnectButton.cxx](#)

## 11.10 car::display::console::component::debug::DebugEnableder Class Reference

### Public Member Functions

- Component [getCheckbox](#) ()
- ComponentDecorator [getWarningModal](#) ()
- const bool & [isEnabled](#) () const

## Private Attributes

- bool `debounce` = false
- bool `enabled` = false
- bool `checkbox_value` = false
- bool `display_warn_debug_modal` = false
- std::string `status` = `DEBUG_MODE_DISABLED_MESSAGE`
- Component `component`

## Static Private Attributes

- static constexpr auto `DEBUG_ENABLE_WARNING_MESSAGE` = "Enabling debug mode temporarily disables connecting to online. Are you sure you want to do this?"
- static constexpr auto `DEBUG_MODE_ENABLED_MESSAGE` = "Debug Status: Enabled"
- static constexpr auto `DEBUG_MODE_DISABLED_MESSAGE` = "Debug Status: Disabled"
- static constexpr auto `DEBUG_MODE_WAIT_MESSAGE` = "Debug Status: Waiting for user input..."

## 11.10.1 Member Function Documentation

### 11.10.1.1 getCheckbox()

Component car::display::console::component::debug::DebugEnabler::getCheckbox ( ) [inline]

### 11.10.1.2 getWarningModal()

ComponentDecorator car::display::console::component::debug::DebugEnabler::getWarningModal ( ) [inline]

### 11.10.1.3 isEnabled()

const bool & car::display::console::component::debug::DebugEnabler::isEnabled ( ) const [inline]

## 11.10.2 Member Data Documentation

### 11.10.2.1 checkbox\_value

bool car::display::console::component::debug::DebugEnabler::checkbox\_value = false [private]

### 11.10.2.2 component

```
Component car::display::console::component::debug::DebugEnabler::component [private]
```

### 11.10.2.3 debounce

```
bool car::display::console::component::debug::DebugEnabler::debounce = false [private]
```

### 11.10.2.4 DEBUG\_ENABLE\_WARNING\_MESSAGE

```
constexpr auto car::display::console::component::debug::DebugEnabler::DEBUG_ENABLE_WARNING_↵  
_MESSAGE = "Enabling debug mode temporarily disables connecting to online. Are you sure you  
want to do this?" [static], [constexpr], [private]
```

### 11.10.2.5 DEBUG\_MODE\_DISABLED\_MESSAGE

```
constexpr auto car::display::console::component::debug::DebugEnabler::DEBUG_MODE_DISABLED_↵  
MESSAGE = "Debug Status: Disabled" [static], [constexpr], [private]
```

### 11.10.2.6 DEBUG\_MODE\_ENABLED\_MESSAGE

```
constexpr auto car::display::console::component::debug::DebugEnabler::DEBUG_MODE_ENABLED_↵  
MESSAGE = "Debug Status: Enabled" [static], [constexpr], [private]
```

### 11.10.2.7 DEBUG\_MODE\_WAIT\_MESSAGE

```
constexpr auto car::display::console::component::debug::DebugEnabler::DEBUG_MODE_WAIT_MESSAGE  
= "Debug Status: Waiting for user input..." [static], [constexpr], [private]
```

### 11.10.2.8 display\_warn\_debug\_modal

```
bool car::display::console::component::debug::DebugEnabler::display_warn_debug_modal = false  
[private]
```

### 11.10.2.9 enabled

```
bool car::display::console::component::debug::DebugEnabler::enabled = false [private]
```

### 11.10.2.10 status

```
std::string car::display::console::component::debug::DebugEnabler::status = DEBUG_MODE_DISABLED_MESSAGE [private]
```

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

- tui/src/car/display/console/component/debug/[DebugEnabler.cxx](#)

## 11.11 car::display::console::component::debug::DebugLidarCheckbox Class Reference

### Public Member Functions

- [DebugLidarCheckbox](#) ()
- Component [element](#) ()
- nod::signal< void(bool)> & [getLidarMotorSignal](#) ()

### Private Attributes

- nod::signal< void(bool)> [lidar\\_motor\\_signal](#)
- std::string [lidar\\_motor\\_status](#) = LIDAR\_MOTOR\_DISABLED\_MESSAGE
- bool [lidar\\_motor\\_loading\\_debounce](#) = false
- bool [lidar\\_motor\\_enabled](#) = false
- Component [lidar\\_motor\\_checkbox\\_component](#)

### Static Private Attributes

- static constexpr auto [LIDAR\\_MOTOR\\_ENABLED\\_MESSAGE](#) = "Lidar Motor Status: Enabled"
- static constexpr auto [LIDAR\\_MOTOR\\_DISABLED\\_MESSAGE](#) = "Lidar Motor Status: Disconnected"

### 11.11.1 Constructor & Destructor Documentation

#### 11.11.1.1 DebugLidarCheckbox()

```
car::display::console::component::debug::DebugLidarCheckbox::DebugLidarCheckbox ( ) [inline]
```

## 11.11.2 Member Function Documentation

### 11.11.2.1 element()

```
Component car::display::console::component::debug::DebugLidarCheckbox::element ( ) [inline]
```

### 11.11.2.2 getLidarMotorSignal()

```
nod::signal< void(bool)> & car::display::console::component::debug::DebugLidarCheckbox::get↔  
LidarMotorSignal ( ) [inline]
```

## 11.11.3 Member Data Documentation

### 11.11.3.1 lidar\_motor\_checkbox\_component

```
Component car::display::console::component::debug::DebugLidarCheckbox::lidar_motor_checkbox_↔  
component [private]
```

### 11.11.3.2 LIDAR\_MOTOR\_DISABLED\_MESSAGE

```
constexpr auto car::display::console::component::debug::DebugLidarCheckbox::LIDAR_MOTOR_↔  
DISABLED_MESSAGE = "Lidar Motor Status: Disconnected" [static], [constexpr], [private]
```

### 11.11.3.3 lidar\_motor\_enabled

```
bool car::display::console::component::debug::DebugLidarCheckbox::lidar_motor_enabled = false  
[private]
```

### 11.11.3.4 LIDAR\_MOTOR\_ENABLED\_MESSAGE

```
constexpr auto car::display::console::component::debug::DebugLidarCheckbox::LIDAR_MOTOR_↔  
ENABLED_MESSAGE = "Lidar Motor Status: Enabled" [static], [constexpr], [private]
```



### 11.11.3.5 lidar\_motor\_loading\_debounce

```
bool car::display::console::component::debug::DebugLidarCheckbox::lidar_motor_loading_debounce
= false [private]
```

### 11.11.3.6 lidar\_motor\_signal

```
nod::signal<void(bool)> car::display::console::component::debug::DebugLidarCheckbox::lidar_↵
motor_signal [private]
```

### 11.11.3.7 lidar\_motor\_status

```
std::string car::display::console::component::debug::DebugLidarCheckbox::lidar_motor_status =
LIDAR_MOTOR_DISABLED_MESSAGE [private]
```

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

- tui/src/car/display/console/component/debug/[DebugLidarCheckbox.cxx](#)

## 11.12 car::display::console::component::debug::DebugMessaging↵ Textbox Class Reference

### Public Member Functions

- [DebugMessagingTextbox](#) (nod::signal< void(const std::string)> &[message\\_signal](#))
- ftxui::Component [element](#) ()

### Private Attributes

- std::string [message](#)
- Component [messaging\\_title](#)
- Component [messaging\\_textbox](#)
- Component [messaging\\_container](#)
- nod::signal< void(const std::string)> & [message\\_signal](#)

### 11.12.1 Constructor & Destructor Documentation

### 11.12.1.1 DebugMessagingTextbox()

```
car::display::console::component::debug::DebugMessagingTextbox::DebugMessagingTextbox (
    nod::signal< void(const std::string)> & message_signal ) [inline]
```

## 11.12.2 Member Function Documentation

### 11.12.2.1 element()

```
ftxui::Component car::display::console::component::debug::DebugMessagingTextbox::element ( )
[inline]
```

## 11.12.3 Member Data Documentation

### 11.12.3.1 message

```
std::string car::display::console::component::debug::DebugMessagingTextbox::message [private]
```

### 11.12.3.2 message\_signal

```
nod::signal<void(const std::string)>& car::display::console::component::debug::DebugMessaging←
Textbox::message_signal [private]
```

### 11.12.3.3 messaging\_container

```
Component car::display::console::component::debug::DebugMessagingTextbox::messaging_container
[private]
```

### 11.12.3.4 messaging\_textbox

```
Component car::display::console::component::debug::DebugMessagingTextbox::messaging_textbox
[private]
```

### 11.12.3.5 messaging\_title

Component car::display::console::component::debug::DebugMessagingTextbox::messaging\_title  
[private]

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

- tui/src/car/display/console/component/debug/DebugMessagingTextbox.cxx

## 11.13 car::display::console::component::debug::DebugMovementRenderer Class Reference

### Public Member Functions

- [DebugMovementRenderer](#) ()
- [ftxui::Component element](#) ()
- [bool updateFrontWheels](#) ()
- [bool updateCameraServo1](#) ()
- [bool updateCameraServo2](#) ()
- [bool updateRearWheels](#) ()
- [nod::signal< void\(bool\)> & getRearWheelDirectionSignal](#) ()
- [const int getFrontWheelsAngleSliderValue](#) () const
- [const int getCameraServo1AngleSliderValue](#) () const
- [const int getCameraServo2AngleSliderValue](#) () const
- [const int getRearLeftWheelSpeedSliderValue](#) () const
- [const int getRearRightWheelSpeedSliderValue](#) () const

### Private Attributes

- [nod::signal< void\(bool\)> rear\\_wheel\\_direction\\_signal](#)
- [int previous\\_rear\\_wheels\\_speed\\_slider\\_value = DEFAULT\\_REAR\\_WHEEL\\_SPEED](#)
- [int rear\\_wheels\\_speed\\_slider\\_value = DEFAULT\\_REAR\\_WHEEL\\_SPEED](#)
- [int previous\\_rear\\_left\\_wheel\\_speed\\_slider\\_value = DEFAULT\\_REAR\\_WHEEL\\_SPEED](#)
- [int rear\\_left\\_wheel\\_speed\\_slider\\_value = DEFAULT\\_REAR\\_WHEEL\\_SPEED](#)
- [int previous\\_rear\\_right\\_wheel\\_speed\\_slider\\_value = DEFAULT\\_REAR\\_WHEEL\\_SPEED](#)
- [int rear\\_right\\_wheel\\_speed\\_slider\\_value = DEFAULT\\_REAR\\_WHEEL\\_SPEED](#)
- [int previous\\_front\\_wheels\\_angle\\_slider\\_value = DEFAULT\\_FRONT\\_WHEEL\\_ANGLE](#)
- [int front\\_wheels\\_angle\\_slider\\_value = DEFAULT\\_FRONT\\_WHEEL\\_ANGLE](#)
- [int previous\\_camera\\_servo\\_1\\_angle\\_slider\\_angle = DEFAULT\\_FRONT\\_WHEEL\\_ANGLE](#)
- [int camera\\_servo\\_1\\_angle\\_slider\\_angle = DEFAULT\\_FRONT\\_WHEEL\\_ANGLE](#)
- [int previous\\_camera\\_servo\\_2\\_angle\\_slider\\_angle = DEFAULT\\_FRONT\\_WHEEL\\_ANGLE](#)
- [int camera\\_servo\\_2\\_angle\\_slider\\_angle = DEFAULT\\_FRONT\\_WHEEL\\_ANGLE](#)
- [bool rear\\_wheel\\_direction\\_debounce = false](#)
- [std::string rear\\_wheel\\_direction\\_status = REAR\\_WHEEL\\_DIRECTION\\_FORWARD\\_MESSAGE](#)
- [bool rear\\_wheel\\_direction = true](#)
- [Component rear\\_wheel\\_speed\\_slider](#)
- [Component rear\\_left\\_wheel\\_speed\\_slider](#)
- [Component rear\\_right\\_wheel\\_speed\\_slider](#)
- [Component rear\\_wheel\\_direction\\_checkbox\\_component](#)
- [Component front\\_wheels\\_angle\\_slider](#)
- [Component camera\\_servo\\_1\\_angle\\_slider](#)
- [Component camera\\_servo\\_2\\_angle\\_slider](#)
- [Component rear\\_wheel\\_menu\\_entry](#)
- [Component servo\\_menu\\_entry](#)
- [Component slider\\_container](#)

## Static Private Attributes

- static constexpr int [DEFAULT\\_REAR\\_WHEEL\\_SPEED](#) = 0
- static constexpr int [DEFAULT\\_FRONT\\_WHEEL\\_ANGLE](#) = 90
- static constexpr auto [REAR\\_WHEEL\\_DIRECTION\\_FORWARD\\_MESSAGE](#) = "Rear Wheel Direction: Forward"
- static constexpr auto [REAR\\_WHEEL\\_DIRECTION\\_BACKWARD\\_MESSAGE](#) = "Rear Wheel Direction: Backward"

## 11.13.1 Constructor & Destructor Documentation

### 11.13.1.1 DebugMovementRenderer()

```
car::display::console::component::debug::DebugMovementRenderer::DebugMovementRenderer ( )
[inline]
```

## 11.13.2 Member Function Documentation

### 11.13.2.1 element()

```
ftxui::Component car::display::console::component::debug::DebugMovementRenderer::element ( )
[inline]
```

### 11.13.2.2 getCameraServo1AngleSliderValue()

```
const int car::display::console::component::debug::DebugMovementRenderer::getCameraServo1↔
AngleSliderValue ( ) const [inline]
```

### 11.13.2.3 getCameraServo2AngleSliderValue()

```
const int car::display::console::component::debug::DebugMovementRenderer::getCameraServo2↔
AngleSliderValue ( ) const [inline]
```

#### 11.13.2.4 getFrontWheelsAngleSliderValue()

```
const int car::display::console::component::debug::DebugMovementRenderer::getFrontWheels↵  
AngleSliderValue ( ) const [inline]
```

#### 11.13.2.5 getRearLeftWheelSpeedSliderValue()

```
const int car::display::console::component::debug::DebugMovementRenderer::getRearLeftWheel↵  
SpeedSliderValue ( ) const [inline]
```

#### 11.13.2.6 getRearRightWheelSpeedSliderValue()

```
const int car::display::console::component::debug::DebugMovementRenderer::getRearRightWheel↵  
SpeedSliderValue ( ) const [inline]
```

#### 11.13.2.7 getRearWheelDirectionSignal()

```
nod::signal< void(bool)> & car::display::console::component::debug::DebugMovementRenderer↵  
::getRearWheelDirectionSignal ( ) [inline]
```

#### 11.13.2.8 updateCameraServo1()

```
bool car::display::console::component::debug::DebugMovementRenderer::updateCameraServo1 ( )  
[inline]
```

#### 11.13.2.9 updateCameraServo2()

```
bool car::display::console::component::debug::DebugMovementRenderer::updateCameraServo2 ( )  
[inline]
```

#### 11.13.2.10 updateFrontWheels()

```
bool car::display::console::component::debug::DebugMovementRenderer::updateFrontWheels ( )  
[inline]
```

#### 11.13.2.11 updateRearWheels()

```
bool car::display::console::component::debug::DebugMovementRenderer::updateRearWheels ( )  
[inline]
```

### 11.13.3 Member Data Documentation

#### 11.13.3.1 camera\_servo\_1\_angle\_slider

```
Component car::display::console::component::debug::DebugMovementRenderer::camera_servo_1_↔  
angle_slider [private]
```

#### 11.13.3.2 camera\_servo\_1\_angle\_slider\_angle

```
int car::display::console::component::debug::DebugMovementRenderer::camera_servo_1_angle_↔  
slider_angle = DEFAULT_FRONT_WHEEL_ANGLE [private]
```

#### 11.13.3.3 camera\_servo\_2\_angle\_slider

```
Component car::display::console::component::debug::DebugMovementRenderer::camera_servo_2_↔  
angle_slider [private]
```

#### 11.13.3.4 camera\_servo\_2\_angle\_slider\_angle

```
int car::display::console::component::debug::DebugMovementRenderer::camera_servo_2_angle_↔  
slider_angle = DEFAULT_FRONT_WHEEL_ANGLE [private]
```

#### 11.13.3.5 DEFAULT\_FRONT\_WHEEL\_ANGLE

```
constexpr int car::display::console::component::debug::DebugMovementRenderer::DEFAULT_FRONT_↔  
WHEEL_ANGLE = 90 [static], [constexpr], [private]
```

### 11.13.3.6 DEFAULT\_REAR\_WHEEL\_SPEED

```
constexpr int car::display::console::component::debug::DebugMovementRenderer::DEFAULT_REAR_WHEEL_SPEED = 0 [static], [constexpr], [private]
```

### 11.13.3.7 front\_wheels\_angle\_slider

```
Component car::display::console::component::debug::DebugMovementRenderer::front_wheels_angle_slider [private]
```

### 11.13.3.8 front\_wheels\_angle\_slider\_value

```
int car::display::console::component::debug::DebugMovementRenderer::front_wheels_angle_slider_value = DEFAULT_FRONT_WHEEL_ANGLE [private]
```

### 11.13.3.9 previous\_camera\_servo\_1\_angle\_slider\_angle

```
int car::display::console::component::debug::DebugMovementRenderer::previous_camera_servo_1_angle_slider_angle = DEFAULT_FRONT_WHEEL_ANGLE [private]
```

### 11.13.3.10 previous\_camera\_servo\_2\_angle\_slider\_angle

```
int car::display::console::component::debug::DebugMovementRenderer::previous_camera_servo_2_angle_slider_angle = DEFAULT_FRONT_WHEEL_ANGLE [private]
```

### 11.13.3.11 previous\_front\_wheels\_angle\_slider\_value

```
int car::display::console::component::debug::DebugMovementRenderer::previous_front_wheels_angle_slider_value = DEFAULT_FRONT_WHEEL_ANGLE [private]
```

### 11.13.3.12 previous\_rear\_left\_wheel\_speed\_slider\_value

```
int car::display::console::component::debug::DebugMovementRenderer::previous_rear_left_wheel_speed_slider_value = DEFAULT_REAR_WHEEL_SPEED [private]
```

#### 11.13.3.13 previous\_rear\_right\_wheel\_speed\_slider\_value

```
int car::display::console::component::debug::DebugMovementRenderer::previous_rear_right_↵  
wheel_speed_slider_value = DEFAULT_REAR_WHEEL_SPEED [private]
```

#### 11.13.3.14 previous\_rear\_wheels\_speed\_slider\_value

```
int car::display::console::component::debug::DebugMovementRenderer::previous_rear_wheels_↵  
speed_slider_value = DEFAULT_REAR_WHEEL_SPEED [private]
```

#### 11.13.3.15 rear\_left\_wheel\_speed\_slider

```
Component car::display::console::component::debug::DebugMovementRenderer::rear_left_wheel_↵  
speed_slider [private]
```

#### 11.13.3.16 rear\_left\_wheel\_speed\_slider\_value

```
int car::display::console::component::debug::DebugMovementRenderer::rear_left_wheel_speed_↵  
slider_value = DEFAULT_REAR_WHEEL_SPEED [private]
```

#### 11.13.3.17 rear\_right\_wheel\_speed\_slider

```
Component car::display::console::component::debug::DebugMovementRenderer::rear_right_wheel_↵  
speed_slider [private]
```

#### 11.13.3.18 rear\_right\_wheel\_speed\_slider\_value

```
int car::display::console::component::debug::DebugMovementRenderer::rear_right_wheel_speed_↵  
slider_value = DEFAULT_REAR_WHEEL_SPEED [private]
```

#### 11.13.3.19 rear\_wheel\_direction

```
bool car::display::console::component::debug::DebugMovementRenderer::rear_wheel_direction =  
true [private]
```



#### 11.13.3.20 REAR\_WHEEL\_DIRECTION\_BACKWARD\_MESSAGE

```
constexpr auto car::display::console::component::debug::DebugMovementRenderer::REAR_WHEEL_↵  
DIRECTION_BACKWARD_MESSAGE = "Rear Wheel Direction: Backward" [static], [constexpr], [private]
```

#### 11.13.3.21 rear\_wheel\_direction\_checkbox\_component

```
Component car::display::console::component::debug::DebugMovementRenderer::rear_wheel_direction_↵  
_checkbox_component [private]
```

#### 11.13.3.22 rear\_wheel\_direction\_debounce

```
bool car::display::console::component::debug::DebugMovementRenderer::rear_wheel_direction_↵  
debounce = false [private]
```

#### 11.13.3.23 REAR\_WHEEL\_DIRECTION\_FORWARD\_MESSAGE

```
constexpr auto car::display::console::component::debug::DebugMovementRenderer::REAR_WHEEL_↵  
DIRECTION_FORWARD_MESSAGE = "Rear Wheel Direction: Forward" [static], [constexpr], [private]
```

#### 11.13.3.24 rear\_wheel\_direction\_signal

```
nod::signal<void(bool)> car::display::console::component::debug::DebugMovementRenderer::rear_↵  
_wheel_direction_signal [private]
```

#### 11.13.3.25 rear\_wheel\_direction\_status

```
std::string car::display::console::component::debug::DebugMovementRenderer::rear_wheel_↵  
direction_status = REAR_WHEEL_DIRECTION_FORWARD_MESSAGE [private]
```

#### 11.13.3.26 rear\_wheel\_menu\_entry

```
Component car::display::console::component::debug::DebugMovementRenderer::rear_wheel_menu_↵  
entry [private]
```

### 11.13.3.27 rear\_wheel\_speed\_slider

```
Component car::display::console::component::debug::DebugMovementRenderer::rear_wheel_speed_slider [private]
```

### 11.13.3.28 rear\_wheels\_speed\_slider\_value

```
int car::display::console::component::debug::DebugMovementRenderer::rear_wheels_speed_slider_value = DEFAULT_REAR_WHEEL_SPEED [private]
```

### 11.13.3.29 servo\_menu\_entry

```
Component car::display::console::component::debug::DebugMovementRenderer::servo_menu_entry [private]
```

### 11.13.3.30 slider\_container

```
Component car::display::console::component::debug::DebugMovementRenderer::slider_container [private]
```

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

- tui/src/car/display/console/component/debug/[DebugMovementRenderer.cxx](#)

## 11.14 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\\_](#)

## 11.14.1 Constructor & Destructor Documentation

### 11.14.1.1 DeviceManager()

```
car::system::device::DeviceManager::DeviceManager (
    std::unique_ptr< CameraDevice > camera\_device,
    std::unique_ptr< lidar::LidarDevice > lidar\_device ) [inline]
```

## 11.14.2 Member Function Documentation

### 11.14.2.1 create()

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

### 11.14.2.2 getCameraDevice()

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

### 11.14.2.3 getLidarDevice()

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

#### 11.14.2.4 initialize()

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

#### 11.14.2.5 isRunning()

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

#### 11.14.2.6 start()

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

#### 11.14.2.7 stop()

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

#### 11.14.2.8 terminate()

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

#### 11.14.2.9 update()

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

### 11.14.3 Member Data Documentation

#### 11.14.3.1 camera\_device\_

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

### 11.14.3.2 car\_system

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

### 11.14.3.3 is\_initialized\_

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

### 11.14.3.4 is\_running\_

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

### 11.14.3.5 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:

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

## 11.15 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

### 11.15.1 Member Function Documentation

#### 11.15.1.1 [initialize\(\)](#)

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

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

#### 11.15.1.2 [setCameraServo1Angle\(\)](#)

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

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

#### 11.15.1.3 [setCameraServo2Angle\(\)](#)

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

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

#### 11.15.1.4 setFrontWheelsAngle()

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

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

#### 11.15.1.5 setRearLeftWheelDirectionToBackward()

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

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

#### 11.15.1.6 setRearLeftWheelDirectionToForward()

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

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

#### 11.15.1.7 setRearLeftWheelSpeed()

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

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

#### 11.15.1.8 setRearRightWheelDirectionToBackward()

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

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

#### 11.15.1.9 setRearRightWheelDirectionToForward()

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

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

#### 11.15.1.10 setRearRightWheelSpeed()

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

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

#### 11.15.1.11 setRearWheelsDirectionToBackward()

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

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

#### 11.15.1.12 setRearWheelsDirectionToForward()

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

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

#### 11.15.1.13 setRearWheelsSpeed()

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

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

#### 11.15.1.14 stop()

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

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



### 11.15.1.15 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:

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

## 11.16 car::system::messaging::MessagingSystem::FirstMessageStruct Struct Reference

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

### Public Attributes

- std::string [error\\_message](#)
- std::string [uuid](#)
- std::condition\_variable [condition](#)

### 11.16.1 Member Data Documentation

#### 11.16.1.1 condition

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

#### 11.16.1.2 error\_message

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

#### 11.16.1.3 uuid

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

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

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

## 11.17 car::configuration::JsonConfiguration Class Reference

### Public Member Functions

- [JsonConfiguration](#) (std::string [exe\\_dir](#))
- void [setConfigFilePath](#) (std::string [config\\_file\\_path](#))
- const std::string & [getConfigFilePath](#) () const
- tl::expected< [Configuration](#), std::string > [loadConfiguration](#) ()

### Private Attributes

- const std::string [exe\\_dir](#)
- std::string [config\\_file\\_path](#)

### 11.17.1 Constructor & Destructor Documentation

#### 11.17.1.1 JsonConfiguration()

```
car::configuration::JsonConfiguration::JsonConfiguration (  
    std::string exe_dir ) [inline]
```

### 11.17.2 Member Function Documentation

#### 11.17.2.1 getConfigFilePath()

```
const std::string & car::configuration::JsonConfiguration::getConfigFilePath ( ) const [inline]
```

#### 11.17.2.2 loadConfiguration()

```
tl::expected< Configuration, std::string > car::configuration::JsonConfiguration::loadConfiguration  
( ) [inline]
```

#### 11.17.2.3 setConfigFilePath()

```
void car::configuration::JsonConfiguration::setConfigFilePath (  
    std::string config_file_path ) [inline]
```

### 11.17.3 Member Data Documentation

#### 11.17.3.1 config\_file\_path

```
std::string car::configuration::JsonConfiguration::config_file_path [private]
```

#### 11.17.3.2 exe\_dir

```
const std::string car::configuration::JsonConfiguration::exe_dir [private]
```

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

- tui/src/car/configuration/[JsonConfiguration.cxx](#)

## 11.18 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](#)

## 11.18.1 Member Function Documentation

### 11.18.1.1 disconnect()

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

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

### 11.18.1.2 getScanData()

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

### 11.18.1.3 initialize()

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

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

### 11.18.1.4 setScanData()

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

### 11.18.1.5 start()

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

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

### 11.18.1.6 stop()

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

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

### 11.18.1.7 terminate()

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

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

### 11.18.1.8 update()

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

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

## 11.18.2 Friends And Related Function Documentation

### 11.18.2.1 DeviceManager

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

## 11.18.3 Member Data Documentation

### 11.18.3.1 scan\_data\_

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

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

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

## 11.19 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

#### 11.19.1 Constructor & Destructor Documentation

##### 11.19.1.1 LidarDummy()

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

#### 11.19.2 Member Function Documentation

##### 11.19.2.1 disconnect()

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

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

### 11.19.2.2 initialize()

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

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

### 11.19.2.3 start()

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

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

### 11.19.2.4 stop()

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

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

### 11.19.2.5 terminate()

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

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

### 11.19.2.6 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:

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

## 11.20 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

#### 11.20.1 Constructor & Destructor Documentation

##### 11.20.1.1 LidarScanner()

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



## 11.20.2 Member Function Documentation

### 11.20.2.1 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]
```

### 11.20.2.2 disconnect()

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

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

### 11.20.2.3 initialize()

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

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

### 11.20.2.4 start()

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

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

### 11.20.2.5 stop()

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

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

### 11.20.2.6 terminate()

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

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

### 11.20.2.7 update()

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

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

## 11.20.3 Member Data Documentation

### 11.20.3.1 configuration\_

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

### 11.20.3.2 lidar\_

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

### 11.20.3.3 running

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

### 11.20.3.4 scan\_data\_

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

### 11.20.3.5 scan\_data\_mutex\_

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

### 11.20.3.6 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:

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

## 11.21 car::display::console::screen::LoggingScreen Class Reference

### Public Member Functions

- [LoggingScreen](#) (std::shared\_ptr< [logging::vector\\_sink\\_mt](#) > [vector\\_sink](#))
- Component [element](#) ()

### Private Attributes

- int [selected\\_line](#) = 0
- std::shared\_ptr< [logging::vector\\_sink\\_mt](#) > [vector\\_sink](#)
- Component [menu](#)
- Component [my\\_custom\\_menu](#)
- ftxui::Elements [line\\_elements](#)

### 11.21.1 Constructor & Destructor Documentation

#### 11.21.1.1 LoggingScreen()

```
car::display::console::screen::LoggingScreen::LoggingScreen (
    std::shared_ptr< logging::vector\_sink\_mt > vector\_sink ) [inline]
```

### 11.21.2 Member Function Documentation

### 11.21.2.1 element()

```
Component car::display::console::screen::LoggingScreen::element ( ) [inline]
```

## 11.21.3 Member Data Documentation

### 11.21.3.1 line\_elements

```
ftxui::Elements car::display::console::screen::LoggingScreen::line_elements [private]
```

### 11.21.3.2 menu

```
Component car::display::console::screen::LoggingScreen::menu [private]
```

### 11.21.3.3 my\_custom\_menu

```
Component car::display::console::screen::LoggingScreen::my_custom_menu [private]
```

### 11.21.3.4 selected\_line

```
int car::display::console::screen::LoggingScreen::selected_line = 0 [private]
```

### 11.21.3.5 vector\_sink

```
std::shared_ptr<logging::vector_sink_mt> car::display::console::screen::LoggingScreen::vector←  
_sink [private]
```

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

- [tui/src/car/display/console/screen/LoggingScreen.cxx](#)

## 11.22 car::display::console::component::main::MainErrorModal Class Reference

### Public Member Functions

- [MainErrorModal](#) ()
- Component [element](#) ()
- void [setErrorMessage](#) (std::string message)

### Public Attributes

- bool [error\\_modal\\_shown](#) = false

### Private Attributes

- Component [main\\_error\\_modal](#)
- Element [error\\_element](#)

### 11.22.1 Constructor & Destructor Documentation

#### 11.22.1.1 MainErrorModal()

```
car::display::console::component::main::MainErrorModal::MainErrorModal ( ) [inline]
```

### 11.22.2 Member Function Documentation

#### 11.22.2.1 element()

```
Component car::display::console::component::main::MainErrorModal::element ( ) [inline]
```

#### 11.22.2.2 setErrorMessage()

```
void car::display::console::component::main::MainErrorModal::setErrorMessage (
    std::string message ) [inline]
```

### 11.22.3 Member Data Documentation

### 11.22.3.1 error\_element

Element car::display::console::component::main::MainErrorModal::error\_element [private]

### 11.22.3.2 error\_modal\_shown

bool car::display::console::component::main::MainErrorModal::error\_modal\_shown = false

### 11.22.3.3 main\_error\_modal

Component car::display::console::component::main::MainErrorModal::main\_error\_modal [private]

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

- tui/src/car/display/console/component/main/[MainErrorModal.cxx](#)

## 11.23 car::display::console::component::main::MainExitModal Class Reference

### Public Member Functions

- [MainExitModal](#) (std::function< void()> [exit](#))
- Component [element](#) ()

### Public Attributes

- bool [exit\\_modal\\_shown](#) = false

### Private Attributes

- std::function< void()> [exit](#)
- Component [main\\_exit\\_modal](#)

## 11.23.1 Constructor & Destructor Documentation

### 11.23.1.1 MainExitModal()

```
car::display::console::component::main::MainExitModal::MainExitModal (
    std::function< void()> exit ) [inline]
```

## 11.23.2 Member Function Documentation

### 11.23.2.1 element()

Component car::display::console::component::main::MainExitModal::element ( ) [inline]

## 11.23.3 Member Data Documentation

### 11.23.3.1 exit

std::function<void()> car::display::console::component::main::MainExitModal::exit [private]

### 11.23.3.2 exit\_modal\_shown

bool car::display::console::component::main::MainExitModal::exit\_modal\_shown = false

### 11.23.3.3 main\_exit\_modal

Component car::display::console::component::main::MainExitModal::main\_exit\_modal [private]

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

- tui/src/car/display/console/component/main/[MainExitModal.cxx](#)

## 11.24 car::display::console::screen::MainScreen Class Reference

### Public Member Functions

- [MainScreen](#) (std::shared\_ptr< [CarSystem](#) > car\_system, std::function< void()> exit)
- Component [element](#) ()

## Private Attributes

- `std::shared_ptr< CarSystem > car_system`
- `Box box`
- `ConnectButton connect_button`
- `MainExitModal main_exit_modal`
- `MainErrorModal main_error_modal`
- `Component info`
- `Component main_screen`
- `Component main_component`

## 11.24.1 Constructor & Destructor Documentation

### 11.24.1.1 MainScreen()

```
car::display::console::screen::MainScreen::MainScreen (
    std::shared_ptr< CarSystem > car_system,
    std::function< void()> exit ) [inline]
```

## 11.24.2 Member Function Documentation

### 11.24.2.1 element()

```
Component car::display::console::screen::MainScreen::element ( ) [inline]
```

## 11.24.3 Member Data Documentation

### 11.24.3.1 box

```
Box car::display::console::screen::MainScreen::box [private]
```

### 11.24.3.2 car\_system

```
std::shared_ptr<CarSystem> car::display::console::screen::MainScreen::car_system [private]
```



### 11.24.3.3 connect\_button

`ConnectButton` car::display::console::screen::MainScreen::connect\_button [private]

### 11.24.3.4 info

`Component` car::display::console::screen::MainScreen::info [private]

### 11.24.3.5 main\_component

`Component` car::display::console::screen::MainScreen::main\_component [private]

### 11.24.3.6 main\_error\_modal

`MainErrorModal` car::display::console::screen::MainScreen::main\_error\_modal [private]

### 11.24.3.7 main\_exit\_modal

`MainExitModal` car::display::console::screen::MainScreen::main\_exit\_modal [private]

### 11.24.3.8 main\_screen

`Component` car::display::console::screen::MainScreen::main\_screen [private]

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

- tui/src/car/display/console/screen/[MainScreen.cxx](#)

## 11.25 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

## 11.25.1 Constructor & Destructor Documentation

### 11.25.1.1 MessagingSystem()

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

## 11.25.2 Member Function Documentation

### 11.25.2.1 getCommandSignal()

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

### 11.25.2.2 getDisconnectSignal()

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

### 11.25.2.3 getFirstMessage()

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

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

#### Returns

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

### 11.25.2.4 getMessageSignal()

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

### 11.25.2.5 getSelectionSignal()

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

#### 11.25.2.6 getUUID()

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

#### 11.25.2.7 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>	
----------------	--

#### 11.25.2.8 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>	
----------------------	--

#### 11.25.2.9 initializeWebSocket()

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

Creates a new WebSocket object for use.

#### 11.25.2.10 isConnected()

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

#### 11.25.2.11 onDisconnect()

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

#### 11.25.2.12 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>	

#### 11.25.2.13 onMessageCallback()

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

#### 11.25.2.14 sendMessage()

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

#### 11.25.2.15 setConfiguration()

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

#### 11.25.2.16 stop()

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

**11.25.2.17 terminate()**

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

**11.25.2.18 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>
```

**11.25.3 Member Data Documentation****11.25.3.1 command\_signal\_**

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

**11.25.3.2 configuration\_**

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

**11.25.3.3 connected\_**

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

**11.25.3.4 message\_signal\_**

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

### 11.25.3.5 on\_disconnect\_signal\_

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

### 11.25.3.6 selection\_signal\_

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

### 11.25.3.7 uuid\_

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

### 11.25.3.8 websocket\_

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

### 11.25.3.9 websocket\_url\_

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

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

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

## 11.26 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](#)

## 11.26.1 Constructor & Destructor Documentation

### 11.26.1.1 MovementSystem()

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

### 11.26.1.2 ~MovementSystem()

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

## 11.26.2 Member Function Documentation

### 11.26.2.1 initialize()

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



### 11.26.2.2 setCameraServo1Angle()

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

### 11.26.2.3 setCameraServo2Angle()

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

### 11.26.2.4 setFrontWheelsAngle()

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

### 11.26.2.5 setRearLeftWheelDirectionToBackward()

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

### 11.26.2.6 setRearLeftWheelDirectionToForward()

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

### 11.26.2.7 setRearLeftWheelSpeed()

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

### 11.26.2.8 setRearRightWheelDirectionToBackward()

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

#### 11.26.2.9 setRearRightWheelDirectionToForward()

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

#### 11.26.2.10 setRearRightWheelSpeed()

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

#### 11.26.2.11 setRearWheelsDirectionToBackward()

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

#### 11.26.2.12 setRearWheelsDirectionToForward()

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

#### 11.26.2.13 setRearWheelsSpeed()

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

#### 11.26.2.14 start()

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

#### 11.26.2.15 stop()

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

### 11.26.2.16 terminate()

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

## 11.26.3 Member Data Documentation

### 11.26.3.1 movement\_controller

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

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

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

## 11.27 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

### 11.27.1 Member Function Documentation

#### 11.27.1.1 getName()

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

Implemented in [behaviour\\_tree::BehaviourTreeHandler](#).

### 11.27.1.2 initialize()

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

Implemented in [behaviour\\_tree::BehaviourTreeHandler](#).

### 11.27.1.3 stop()

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

Implemented in [behaviour\\_tree::BehaviourTreeHandler](#).

### 11.27.1.4 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:

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

## 11.28 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](#)

## 11.28.1 Member Function Documentation

### 11.28.1.1 addPlugin()

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

### 11.28.1.2 getPlugin()

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

### 11.28.1.3 initialize()

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

### 11.28.1.4 stop()

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

### 11.28.1.5 terminate()

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

### 11.28.1.6 update()

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

## 11.28.2 Member Data Documentation

### 11.28.2.1 plugins

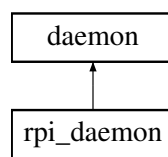
```
std::vector<std::shared_ptr<Plugin> > car::plugin::PluginManager::plugins [private]
```

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

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

## 11.29 rpi\_daemon Class Reference

Inheritance diagram for rpi\_daemon:



### Public Member Functions

- void [on\\_start](#) (const INIReader reader) override
- void [update](#) ()
- void [connect](#) (const std::chrono::time\_point< std::chrono::steady\_clock > &now)
- void [on\\_update](#) () override
- void [on\\_stop](#) () override
- void [on\\_reload](#) (const INIReader reader) override

### Private Attributes

- std::shared\_ptr< [CarSystem](#) > [car\\_system](#)
- bool [any\\_configuration\\_empty](#) = false
- bool [attempted\\_to\\_reconnect](#) = false
- std::chrono::milliseconds [connection\\_ms\\_interval](#) = std::chrono::milliseconds(1000)
- std::chrono::time\_point< std::chrono::steady\_clock > [last\\_connected](#)

## 11.29.1 Member Function Documentation

### 11.29.1.1 connect()

```
void rpi_daemon::connect (
    const std::chrono::time_point< std::chrono::steady_clock > & now ) [inline]
```

### 11.29.1.2 on\_reload()

```
void rpi_daemon::on_reload (
    const INIReader reader ) [inline], [override]
```

### 11.29.1.3 on\_start()

```
void rpi_daemon::on_start (
    const INIReader reader ) [inline], [override]
```

### 11.29.1.4 on\_stop()

```
void rpi_daemon::on_stop ( ) [inline], [override]
```

### 11.29.1.5 on\_update()

```
void rpi_daemon::on_update ( ) [inline], [override]
```

### 11.29.1.6 update()

```
void rpi_daemon::update ( ) [inline]
```

## 11.29.2 Member Data Documentation

### 11.29.2.1 any\_configuration\_empty

```
bool rpi_daemon::any_configuration_empty = false [private]
```

### 11.29.2.2 attempted\_to\_reconnect

```
bool rpi_daemon::attempted_to_reconnect = false [private]
```

### 11.29.2.3 car\_system

```
std::shared_ptr<CarSystem> rpi_daemon::car_system [private]
```

### 11.29.2.4 connection\_ms\_interval

```
std::chrono::milliseconds rpi_daemon::connection_ms_interval = std::chrono::milliseconds(1000)
[private]
```

### 11.29.2.5 last\_connected

```
std::chrono::time_point<std::chrono::steady_clock> rpi_daemon::last_connected [private]
```

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

- daemon/src/main.cpp

## 11.30 car::display::console::component::settings::SettingsEditConfig Class Reference

### Public Member Functions

- [SettingsEditConfig](#) (std::shared\_ptr< [system::CarSystem](#) > [car\\_system](#), std::shared\_ptr< [JsonConfiguration](#) > [json\\_configuration](#))
- Component [element](#) ()

### Private Attributes

- std::shared\_ptr< [system::CarSystem](#) > [car\\_system](#)
- std::shared\_ptr< [configuration::JsonConfiguration](#) > [json\\_configuration](#)
- std::string [placeholder](#) = "settings/config.jsonc"
- std::string [settings\\_file\\_path](#) = "settings/config.jsonc"
- Component [input\\_settings\\_file\\_path](#)
- Component [load\\_button](#)

### 11.30.1 Constructor & Destructor Documentation



### 11.30.1.1 SettingsEditConfig()

```
car::display::console::component::settings::SettingsEditConfig::SettingsEditConfig (
    std::shared_ptr< system::CarSystem > car_system,
    std::shared_ptr< JsonConfiguration > json_configuration ) [inline]
```

## 11.30.2 Member Function Documentation

### 11.30.2.1 element()

```
Component car::display::console::component::settings::SettingsEditConfig::element ( ) [inline]
```

## 11.30.3 Member Data Documentation

### 11.30.3.1 car\_system

```
std::shared_ptr<system::CarSystem> car::display::console::component::settings::SettingsEdit↔
Config::car_system [private]
```

### 11.30.3.2 input\_settings\_file\_path

```
Component car::display::console::component::settings::SettingsEditConfig::input_settings↔
file_path [private]
```

### 11.30.3.3 json\_configuration

```
std::shared_ptr<configuration::JsonConfiguration> car::display::console::component::settings↔
::SettingsEditConfig::json_configuration [private]
```

### 11.30.3.4 load\_button

```
Component car::display::console::component::settings::SettingsEditConfig::load_button [private]
```

### 11.30.3.5 placeholder

```
std::string car::display::console::component::settings::SettingsEditConfig::placeholder =
"settings/config.jsonc" [private]
```

### 11.30.3.6 settings\_file\_path

```
std::string car::display::console::component::settings::SettingsEditConfig::settings_file_path
= "settings/config.jsonc" [private]
```

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

- tui/src/car/display/console/component/settings/[SettingsEditConfig.cxx](#)

## 11.31 car::display::console::screen::SettingsScreen Class Reference

### Public Member Functions

- [SettingsScreen](#) (std::shared\_ptr< [CarSystem](#) > car\_system, std::shared\_ptr< [JsonConfiguration](#) > json\_configuration)
- Component [element](#) ()
- void [update](#) ()

### Private Attributes

- std::shared\_ptr< [CarSystem](#) > car\_system
- [SettingsEditConfig](#) settings\_edit\_config
- [DebugEnabler](#) debug\_enabler
- [DebugLidarCheckbox](#) debug\_lidar\_checkbox
- [DebugMovementRenderer](#) debug\_movement\_renderer
- [DebugMessagingTextbox](#) debug\_messaging\_text\_box

## 11.31.1 Constructor & Destructor Documentation

### 11.31.1.1 SettingsScreen()

```
car::display::console::screen::SettingsScreen::SettingsScreen (
    std::shared_ptr< CarSystem > car_system,
    std::shared_ptr< JsonConfiguration > json_configuration ) [inline]
```

## 11.31.2 Member Function Documentation

### 11.31.2.1 element()

Component car::display::console::screen::SettingsScreen::element ( ) [inline]

### 11.31.2.2 update()

void car::display::console::screen::SettingsScreen::update ( ) [inline]

## 11.31.3 Member Data Documentation

### 11.31.3.1 car\_system

std::shared\_ptr<CarSystem> car::display::console::screen::SettingsScreen::car\_system [private]

### 11.31.3.2 debug\_enabler

DebugEnabledler car::display::console::screen::SettingsScreen::debug\_enabler [private]

### 11.31.3.3 debug\_lidar\_checkbox

DebugLidarCheckbox car::display::console::screen::SettingsScreen::debug\_lidar\_checkbox [private]

### 11.31.3.4 debug\_messaging\_text\_box

DebugMessagingTextbox car::display::console::screen::SettingsScreen::debug\_messaging\_text\_box  
[private]

### 11.31.3.5 debug\_movement\_renderer

`DebugMovementRenderer` `car::display::console::screen::SettingsScreen::debug_movement_renderer`  
[private]

### 11.31.3.6 settings\_edit\_config

`SettingsEditConfig` `car::display::console::screen::SettingsScreen::settings_edit_config` [private]

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

- `tui/src/car/display/console/screen/SettingsScreen.cxx`

## 11.32 TB6612 Class Reference

```
#include <TB6612.h>
```

### Public Member Functions

- `TB6612` (int `motor_pin`, int `pwm_pin`)
- void `setPWM` (int value)
- void `forward` ()
- void `backward` ()
- void `stop` ()
- void `setOffset` (bool `offset`)
- const int & `getMotorPin` () const
- const int & `getPWMPin` () const

### Private Attributes

- const int `motor_pin`
- const int `pwm_pin`
- bool `offset` = true

### 11.32.1 Constructor & Destructor Documentation

#### 11.32.1.1 TB6612()

```
TB6612::TB6612 (
    int motor_pin,
    int pwm_pin )
```

## 11.32.2 Member Function Documentation

### 11.32.2.1 backward()

```
void TB6612::backward ( )
```

### 11.32.2.2 forward()

```
void TB6612::forward ( )
```

### 11.32.2.3 getMotorPin()

```
const int & TB6612::getMotorPin ( ) const
```

### 11.32.2.4 getPWMPin()

```
const int & TB6612::getPWMPin ( ) const
```

### 11.32.2.5 setOffset()

```
void TB6612::setOffset (
    bool offset )
```

### 11.32.2.6 setPWM()

```
void TB6612::setPWM (
    int value )
```

### 11.32.2.7 stop()

```
void TB6612::stop ( )
```

### 11.32.3 Member Data Documentation

#### 11.32.3.1 motor\_pin

```
const int TB6612::motor_pin [private]
```

#### 11.32.3.2 offset

```
bool TB6612::offset = true [private]
```

#### 11.32.3.3 pwm\_pin

```
const int TB6612::pwm_pin [private]
```

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

- repository/packages/t/tb6612/tb6612/include/[TB6612.h](#)
- repository/packages/t/tb6612/tb6612/src/[TB6612.cpp](#)

## 11.33 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](#)

## 11.33.1 Constructor & Destructor Documentation

### 11.33.1.1 VectorSink()

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

## 11.33.2 Member Function Documentation

### 11.33.2.1 flush\_()

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

### 11.33.2.2 get\_log\_messages()

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

### 11.33.2.3 sink\_it\_()

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

## 11.33.3 Member Data Documentation

### 11.33.3.1 log\_messages

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

### 11.33.3.2 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:

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



## Chapter 12

# File Documentation

### 12.1 behaviour\_tree/src/main.cpp File Reference

```
#include <iostream>
#include <chrono>
#include <filesystem>
#include <memory>
#include <cxxopts.hpp>
#include "car/system/CarSystem.h"
#include "car/system/device/lidar/LidarScanner.h"
#include "car/system/device/lidar/LidarDummy.h"
#include "car/system/movement/controller/DummyMovementController.h"
#include "car/system/movement/controller/DeviceMovementController.h"
#include "car/plugin/PluginManager.h"
#include "behaviour_tree/BehaviourTreeParser.hpp"
#include "behaviour_tree/node/custom/CarCustomNodeParser.hpp"
#include "behaviour_tree/BehaviourTreeHandler.hpp"
#include <thread>
#include <unistd.h>
#include <termios.h>
```

#### Functions

- int [kbhit](#) (void)
- int [main](#) (int argc, const char \*argv[])

#### 12.1.1 Function Documentation

##### 12.1.1.1 kbhit()

```
int kbhit (
    void )
```

### 12.1.1.2 main()

```
int main (
    int argc,
    const char * argv[] )
```

## 12.2 daemon/src/main.cpp File Reference

```
#include <iostream>
#include <chrono>
#include <filesystem>
#include <memory>
#include <daemonpp/daemon.hpp>
#include <cpptrace/cpptrace.hpp>
#include <fmt/format.h>
#include <spdlog/sinks/callback_sink.h>
#include "car/system/CarSystem.h"
#include "car/system/device/lidar/LidarScanner.h"
#include "car/system/device/lidar/LidarDummy.h"
#include "car/system/movement/controller/DummyMovementController.h"
#include "car/system/movement/controller/DeviceMovementController.h"
#include "behaviour_tree/BehaviourTreeHandler.hpp"
#include "car/plugin/PluginManager.h"
```

### Classes

- class [rpi\\_daemon](#)

### Functions

- `std::unique_ptr< LidarDevice > getLidarDevice (std::shared_ptr< Configuration > configuration)`
- `std::unique_ptr< AbstractMovementController > getMovementController ()`
- `void terminate\_handler ()`
- `int main (int argc, const char *argv[])`

### 12.2.1 Function Documentation

#### 12.2.1.1 getLidarDevice()

```
std::unique_ptr< lidar::LidarDevice > getLidarDevice (
    std::shared_ptr< Configuration > configuration )
```

### 12.2.1.2 getMovementController()

```
std::unique_ptr< AbstractMovementController > getMovementController ( )
```

### 12.2.1.3 main()

```
int main (
    int argc,
    const char * argv[] )
```

### 12.2.1.4 terminate\_handler()

```
void terminate_handler ( )
```

## 12.3 tui/src/main.cpp File Reference

```
#include <optional>
#include <string>
#include <thread>
#include <chrono>
#include <fmt/format.h>
#include "car/display/console/CarConsole.h"
#include "car/configuration/JsonConfiguration.cxx"
#include "car/system/CarSystem.h"
#include "car/system/device/DeviceManager.h"
#include "car/system/device/lidar/LidarDevice.h"
#include "car/system/device/lidar/LidarDummy.h"
#include "car/system/device/lidar/LidarScanner.h"
#include "car/system/device/CameraDevice.h"
#include "car/system/movement/controller/DummyMovementController.h"
#include "car/system/movement/controller/DeviceMovementController.h"
#include "car/plugin/PluginManager.h"
#include "car/system/logging/VectorSink.h"
#include "behaviour_tree/BehaviourTreeHandler.hpp"
```

## Functions

- `std::unique_ptr< LidarDevice > getLidarDevice (std::shared_ptr< Configuration > configuration)`
- `std::unique_ptr< AbstractMovementController > getMovementController ()`
- `int main (int argc, char *argv[])`

### 12.3.1 Function Documentation

### 12.3.1.1 `getLidarDevice()`

```
std::unique_ptr< LidarDevice > getLidarDevice (
    std::shared_ptr< Configuration > configuration )
```

### 12.3.1.2 `getMovementController()`

```
std::unique_ptr< AbstractMovementController > getMovementController ( )
```

### 12.3.1.3 `main()`

```
int main (
    int argc,
    char * argv[] )
```

## 12.4 `common/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](#)

## 12.5 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>(CarCustomNodeParser));
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                 spdlog::error(R"(The property "action" does not match "set" or "start", {})", action);
70                 break;
71             };
72         }
73
74         void setBehaviourTree(const rapidjson::Document &message_json)
75         {
76             if (!message_json.HasMember("data") || !message_json["data"].IsString())
77             {
78                 spdlog::error(R"(The property "data" does not exist in the given json.)");
79                 return;
80             }
81             try
82             {
83

```

```

79         auto maybe_behaviour_tree =
BehaviourTreeParser::instance().parseXML(message_json["data"].GetString());
80         if (!maybe_behaviour_tree.has_value())
81         {
82             spdlog::error(R"(Unable to parse the given behaviour tree | {})",
maybe_behaviour_tree.error());
83             return;
84         }
85         auto &behaviour_tree = maybe_behaviour_tree.value();
86         spdlog::info("Behaviour tree parsed successfully | {}", behaviour_tree->toString());
87         this->_setBehaviourTree(behaviour_tree);
88     }
89     catch (std::exception &e)
90     {
91         spdlog::error("An error has occurred while parsing the given behaviour tree: {}",
e.what());
92     }
93 }
94
95 void startBehaviourTree()
96 {
97     assert(this->car_system != nullptr);
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

```

## 12.6 common/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`

## 12.7 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

```

## 12.8 common/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](#)

## 12.9 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
```

## 12.10 common/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](#)

## 12.11 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
```

## 12.12 common/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](#)

## 12.13 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
82 #endif

```

## 12.14 common/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](#)

## 12.15 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

```

## 12.16 common/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](#)

## 12.17 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) :
20             configuration(configuration) {}
21
22         CameraDevice(const CameraDevice&) = delete;
23         CameraDevice& operator=(const CameraDevice&) = delete;
24
25         CameraDevice(CameraDevice&&) = delete;
26         CameraDevice& operator=(CameraDevice&&) = delete;
27
28         ~CameraDevice() = default;
29
30     public:
31         [[nodiscard]] static tl::expected<std::unique_ptr<CameraDevice>, std::string>
32             create(std::shared_ptr<configuration::Configuration> configuration);
33         std::string getFrameBuffer() const;
34
35     protected:
36         void start();
37         void update();
38         void stop();
39         void disconnect();
40         void terminate();
41
42     friend class DeviceManager;
43
44     private:
45         std::shared_ptr<configuration::Configuration> configuration;
46
47         std::unique_ptr<cv::VideoCapture> camera_;
48
49         bool connected_ = false;
50         std::string frame_buffer_;
51
52         std::mutex camera_mutex_;
53
54         std::chrono::steady_clock::time_point last;
55     };
56 }
57 #endif

```

## 12.18 common/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`

## 12.19 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

```

## 12.20 common/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](#)

## 12.21 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
```

## 12.22 common/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](#)

## 12.23 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
```

## 12.24 common/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`

## 12.25 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             auto maybe_lidar = RPLidar::create(configuration->lidar_port);
27             if (maybe_lidar.has_value())
28             {
29                 return std::make_unique<LidarScanner>(configuration, std::move(maybe_lidar.value()));
30             }
31             else
32             {
33                 return tl::make_unexpected(maybe_lidar.error());
34             }
35         }
36
37         // Do not call this constructor directly. Use the create method instead.
38         LidarScanner(std::shared_ptr<configuration::Configuration> configuration,
39                     std::unique_ptr<RPLidar> lidar) : configuration_(configuration), lidar_(std::move(lidar)) {}
40
41         void start() final override
42         {
43             this->running = true;
44             this->lidar_->start_motor();
45             std::lock_guard<std::mutex> lock(this->scan_data_mutex_);
46             this->scan_generator_ = this->lidar_->iter_scans();
47         }
48
49         void update() final override
50         {
51             if (this->running) {
52                 std::lock_guard<std::mutex> lock(this->scan_data_mutex_);
53                 const auto& scan_generator =
54                     std::get<std::function<std::vector<Measure>()>>(this->scan_generator_);
55                 this->set_scan_data(scan_generator());
56             }
57         }
58
59         void stop() final override

```

```

58     {
59         if (this->running) {
60             this->running = false;
61             std::lock_guard<std::mutex> lock(this->scan_data_mutex_);
62             this->scan_generator_ = nullptr;
63             this->lidar_->stop();
64             this->lidar_->stop_motor();
65         }
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

```

## 12.26 common/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 >`

## 12.27 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         std::vector<std::string> log_messages;
53     };
54     using vector_sink_mt = VectorSink<std::mutex>;
55 }
56 #endif

```

## 12.28 common/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](#)

## 12.29 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

```

## 12.30 common/include/car/system/messaging/StreamType.h File Reference

### Enumerations

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

### 12.30.1 Enumeration Type Documentation

#### 12.30.1.1 StreamType

enum [StreamType](#)

##### Enumerator

None	
Lidar	
Camera	
Both	

## 12.31 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
```

## 12.32 common/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](#)

## 12.33 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
```

## 12.34 common/include/car/system/movement/controller/DeviceMovementController.h File Reference

### 12.35 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__
```

## 12.36 common/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`

## 12.37 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
```



## 12.38 common/include/car/system/movement/devices/RearWheel.h File Reference

### 12.39 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

```

## 12.40 common/include/car/system/movement/devices/Servo.h File Reference

### 12.41 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 }
21

```

```

22     }
23
24     static constexpr int MIN_PULSE_WIDTH = 900;
25     static constexpr int MAX_PULSE_WIDTH = 2100;
26     static constexpr int FREQUENCY = 50;
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__

```

## 12.42 common/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](#)

## 12.43 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) :
            movement_controller(std::move(movement_controller)) {};
18
19         void initialize()
20         {
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
```

## 12.44 common/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](#)

## 12.45 common/src/car/system/device/CameraDevice.cpp File Reference

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

### Namespaces

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

## 12.46 common/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](#)

## 12.47 common/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](#)

## 12.48 common/src/car/system/movement/controller/DeviceMovementController.cpp File Reference ↩

## 12.49 common/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](#)

## 12.50 common/src/car/system/movement/devices/RearWheel.cpp File Reference

## 12.51 common/src/car/system/movement/devices/Servo.cpp File Reference

## 12.52 common/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

### 12.52.1 Function Documentation

#### 12.52.1.1 main()

```
int main ( )
```

#### 12.52.1.2 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

### 12.52.1.3 `setAngle()`

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

### 12.52.1.4 `setAngleToAnalog()`

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

## 12.52.2 Variable Documentation

### 12.52.2.1 `offset`

```
int offset = 0
```

## 12.53 common/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](#) ()

### 12.53.1 Function Documentation

### 12.53.1.1 main()

```
int main ( )
```

### 12.53.1.2 test()

```
void test ( )
```

## 12.54 daemon/install/README.md File Reference

## 12.55 daemon/README.md File Reference

## 12.56 README.md File Reference

## 12.57 tui/README.md File Reference

## 12.58 repository/packages/t/tb6612/tb6612/include/TB6612.h File Reference

```
#include "pigpio.h"  
#include "pigpiod_if2.h"
```

### Classes

- class [TB6612](#)

## 12.59 TB6612.h

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

```
1 #ifndef TB6612_HPP  
2 #define TB6612_HPP  
3  
4 #pragma once  
5  
6 // Made with the help of ChatGPT  
7  
8 #include "pigpio.h"  
9 #include "pigpiod_if2.h"  
10  
11 class TB6612  
12 {  
13 public:  
14     TB6612(int motor_pin, int pwm_pin);  
15  
16     void setPWM(int value);  
17
```



```
18     void forward();
19
20     void backward();
21
22     void stop();
23
24     void setOffset(bool offset);
25
26     const int &getMotorPin() const;
27
28     const int &getPWMPin() const;
29
30 private:
31     const int motor_pin;
32     const int pwm_pin;
33     bool offset = true;
34 };
35
36 #endif
```

## 12.60 repository/packages/t/tb6612/tb6612/src/TB6612.cpp File Reference

```
#include "TB6612.h"
```

## 12.61 SETUP.md File Reference

## 12.62 tui/src/car/configuration/JsonConfiguration.cxx File Reference

```
#include <iostream>
#include <fstream>
#include <variant>
#include <optional>
#include <rapidjson/document.h>
#include <rapidjson/istreamwrapper.h>
#include <spdlog/spdlog.h>
#include <fmt/format.h>
#include <tl/expected.hpp>
#include "car/configuration/Configuration.h"
```

### Classes

- class [car::configuration::JsonConfiguration](#)

### Namespaces

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

### Macros

- [#define JSONCONFIGURATION\\_CXX](#)

## 12.62.1 Macro Definition Documentation

### 12.62.1.1 JSONCONFIGURATION\_CXX

```
#define JSONCONFIGURATION_CXX
```

## 12.63 tui/src/car/display/console/CarConsole.cpp File Reference

```
#include "CarConsole.h"  
#include <ftxui/component/component.hpp>  
#include <ftxui/component/screen_interactive.hpp>  
#include <ftxui/dom/elements.hpp>  
#include <ftxui/component/loop.hpp>  
#include <nod/nod.hpp>
```

### Namespaces

- namespace [car](#)
- namespace [car::display](#)
- namespace [car::display::console](#)

## 12.64 tui/src/car/display/console/CarConsole.h File Reference

```
#include <memory>  
#include "car/system/CarSystem.h"  
#include "car/system/logging/VectorSink.h"  
#include "screen/MainScreen.cxx"  
#include "screen/SettingsScreen.cxx"  
#include "screen/LoggingScreen.cxx"
```

### Classes

- class [car::display::console::CarConsole](#)

### Namespaces

- namespace [car](#)
- namespace [car::display](#)
- namespace [car::display::console](#)

## 12.65 CarConsole.h

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

```

1 #ifndef CARCONSOLE_H
2 #define CARCONSOLE_H
3
4 #pragma once
5
6 #include <memory>
7
8 #include "car/system/CarSystem.h"
9 #include "car/system/logging/VectorSink.h"
10
11 #include "screen/MainScreen.cxx"
12 #include "screen/SettingsScreen.cxx"
13 #include "screen/LoggingScreen.cxx"
14
15 using namespace car::system;
16 using namespace car::display::console::screen;
17
18 namespace car::display::console
19 {
20     class CarConsole
21     {
22     public:
23         CarConsole(std::shared_ptr<CarSystem> car_system, std::shared_ptr<JsonConfiguration>
                json_configuration, std::shared_ptr<logging::vector_sink_mt> vector_sink);
24
25         void initialize();
26
27         void run();
28
29         void terminate();
30
31     private:
32         std::shared_ptr<CarSystem> car_system;
33         std::shared_ptr<JsonConfiguration> json_configuration;
34         std::shared_ptr<logging::vector_sink_mt> vector_sink;
35     };
36 }
37
38 #endif

```

## 12.66 tui/src/car/display/console/component/debug/DebugEnabler.cxx

### File Reference

```

#include <nod/nod.hpp>
#include <ftxui/component/component.hpp>

```

### Classes

- class [car::display::console::component::debug::DebugEnabler](#)

### Namespaces

- namespace [car](#)
- namespace [car::display](#)
- namespace [car::display::console](#)
- namespace [car::display::console::component](#)
- namespace [car::display::console::component::debug](#)

### Macros

- #define [DEBUGENABLER\\_CXX](#)

## 12.66.1 Macro Definition Documentation

### 12.66.1.1 DEBUGENABLER\_CXX

```
#define DEBUGENABLER_CXX
```

## 12.67 [tui/src/car/display/console/component/debug/DebugLidar](#)↔ Checkbox.cxx File Reference

```
#include <nod/nod.hpp>  
#include <ftxui/component/component.hpp>
```

### Classes

- class [car::display::console::component::debug::DebugLidarCheckbox](#)

### Namespaces

- namespace [car](#)
- namespace [car::display](#)
- namespace [car::display::console](#)
- namespace [car::display::console::component](#)
- namespace [car::display::console::component::debug](#)

### Macros

- #define [DEBUGLIDARCHECKBOX\\_CXX](#)

## 12.67.1 Macro Definition Documentation

### 12.67.1.1 DEBUGLIDARCHECKBOX\_CXX

```
#define DEBUGLIDARCHECKBOX_CXX
```

## 12.68 tui/src/car/display/console/component/debug/DebugMessagingTextbox.cxx File Reference

```
#include <nod/nod.hpp>
#include <ftxui/component/component.hpp>
```

### Classes

- class [car::display::console::component::debug::DebugMessagingTextbox](#)

### Namespaces

- namespace [car](#)
- namespace [car::display](#)
- namespace [car::display::console](#)
- namespace [car::display::console::component](#)
- namespace [car::display::console::component::debug](#)

### Macros

- `#define` [DEBUGMESSAGINGTEXTBOX\\_CXX](#)

### 12.68.1 Macro Definition Documentation

#### 12.68.1.1 DEBUGMESSAGINGTEXTBOX\_CXX

```
#define DEBUGMESSAGINGTEXTBOX_CXX
```

## 12.69 tui/src/car/display/console/component/debug/DebugMovementRenderer.cxx File Reference

```
#include <nod/nod.hpp>
#include <ftxui/component/component.hpp>
```

### Classes

- class [car::display::console::component::debug::DebugMovementRenderer](#)

## Namespaces

- namespace [car](#)
- namespace [car::display](#)
- namespace [car::display::console](#)
- namespace [car::display::console::component](#)
- namespace [car::display::console::component::debug](#)

## Macros

- `#define` [DEBUGMOVEMENTRENDERER\\_CXX](#)

### 12.69.1 Macro Definition Documentation

#### 12.69.1.1 DEBUGMOVEMENTRENDERER\_CXX

```
#define DEBUGMOVEMENTRENDERER_CXX
```

## 12.70 tui/src/car/display/console/component/main/ConnectButton.cxx File Reference

```
#include <ftxui/component/component.hpp>  
#include "car/system/CarSystem.h"
```

## Classes

- class [car::display::console::component::main::ConnectButton](#)

## Namespaces

- namespace [car](#)
- namespace [car::display](#)
- namespace [car::display::console](#)
- namespace [car::display::console::component](#)
- namespace [car::display::console::component::main](#)

## Macros

- `#define` [CONNECTBUTTON\\_CXX](#)

## 12.70.1 Macro Definition Documentation

### 12.70.1.1 CONNECTBUTTON\_CXX

```
#define CONNECTBUTTON_CXX
```

## 12.71 tui/src/car/display/console/component/main/MainErrorModal.cxx File Reference

```
#include <ftxui/component/component.hpp>  
#include "car/system/CarSystem.h"
```

### Classes

- class [car::display::console::component::main::MainErrorModal](#)

### Namespaces

- namespace [car](#)
- namespace [car::display](#)
- namespace [car::display::console](#)
- namespace [car::display::console::component](#)
- namespace [car::display::console::component::main](#)

### Macros

- #define [MAINERRORMODAL\\_CXX](#)

## 12.71.1 Macro Definition Documentation

### 12.71.1.1 MAINERRORMODAL\_CXX

```
#define MAINERRORMODAL_CXX
```

## 12.72 tui/src/car/display/console/component/main/MainExitModal.cxx File Reference

```
#include <ftxui/component/component.hpp>
#include "car/system/CarSystem.h"
```

### Classes

- class [car::display::console::component::main::MainExitModal](#)

### Namespaces

- namespace [car](#)
- namespace [car::display](#)
- namespace [car::display::console](#)
- namespace [car::display::console::component](#)
- namespace [car::display::console::component::main](#)

### Macros

- #define [MAINEXITMODAL\\_CXX](#)

## 12.72.1 Macro Definition Documentation

### 12.72.1.1 MAINEXITMODAL\_CXX

```
#define MAINEXITMODAL_CXX
```

## 12.73 tui/src/car/display/console/component/settings/SettingsEdit↵ Config.cxx File Reference

```
#include <ftxui/component/component.hpp>
#include "car/system/CarSystem.h"
#include "../../../../../configuration/JsonConfiguration.cxx"
```

### Classes

- class [car::display::console::component::settings::SettingsEditConfig](#)



## Namespaces

- namespace [car](#)
- namespace [car::display](#)
- namespace [car::display::console](#)
- namespace [car::display::console::component](#)
- namespace [car::display::console::component::settings](#)

## Macros

- `#define` [SETTINGSEEDITCONFIG\\_CXX](#)

### 12.73.1 Macro Definition Documentation

#### 12.73.1.1 SETTINGSEEDITCONFIG\_CXX

```
#define SETTINGSEEDITCONFIG_CXX
```

## 12.74 tui/src/car/display/console/screen/LoggingScreen.cxx File Reference

```
#include <ftxui/component/component.hpp>  
#include <spdlog/spdlog.h>  
#include "car/system/logging/VectorSink.h"
```

## Classes

- class [car::display::console::screen::LoggingScreen](#)

## Namespaces

- namespace [car](#)
- namespace [car::display](#)
- namespace [car::display::console](#)
- namespace [car::display::console::screen](#)

## Macros

- `#define` [LOGGINGSCREEN\\_CXX](#)

## 12.74.1 Macro Definition Documentation

### 12.74.1.1 LOGGINGSCREEN\_CXX

```
#define LOGGINGSCREEN_CXX
```

## 12.75 tui/src/car/display/console/screen/MainScreen.cxx File Reference

```
#include <memory>
#include <ftxui/component/component.hpp>
#include "car/system/CarSystem.h"
#include "../component/main/ConnectButton.cxx"
#include "../component/main/MainExitModal.cxx"
#include "../component/main/MainErrorModal.cxx"
```

### Classes

- class [car::display::console::screen::MainScreen](#)

### Namespaces

- namespace [car](#)
- namespace [car::display](#)
- namespace [car::display::console](#)
- namespace [car::display::console::screen](#)

### Macros

- #define [MAINSCREEN\\_CXX](#)

## 12.75.1 Macro Definition Documentation

### 12.75.1.1 MAINSCREEN\_CXX

```
#define MAINSCREEN_CXX
```

## 12.76 tui/src/car/display/console/screen/SettingsScreen.cxx File Reference

```
#include <memory>
#include <ftxui/component/component.hpp>
#include "car/system/CarSystem.h"
#include "../../configuration/JsonConfiguration.cxx"
#include "../component/settings/SettingsEditConfig.cxx"
#include "../component/debug/DebugEnabler.cxx"
#include "../component/debug/DebugLidarCheckbox.cxx"
#include "../component/debug/DebugMovementRenderer.cxx"
#include "../component/debug/DebugMessagingTextbox.cxx"
```

### Classes

- class [car::display::console::screen::SettingsScreen](#)

### Namespaces

- namespace [car](#)
- namespace [car::display](#)
- namespace [car::display::console](#)
- namespace [car::display::console::screen](#)

### Macros

- #define [SETTINGSSCREEN\\_CXX](#)

#### 12.76.1 Macro Definition Documentation

##### 12.76.1.1 SETTINGSSCREEN\_CXX

```
#define SETTINGSSCREEN_CXX
```



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