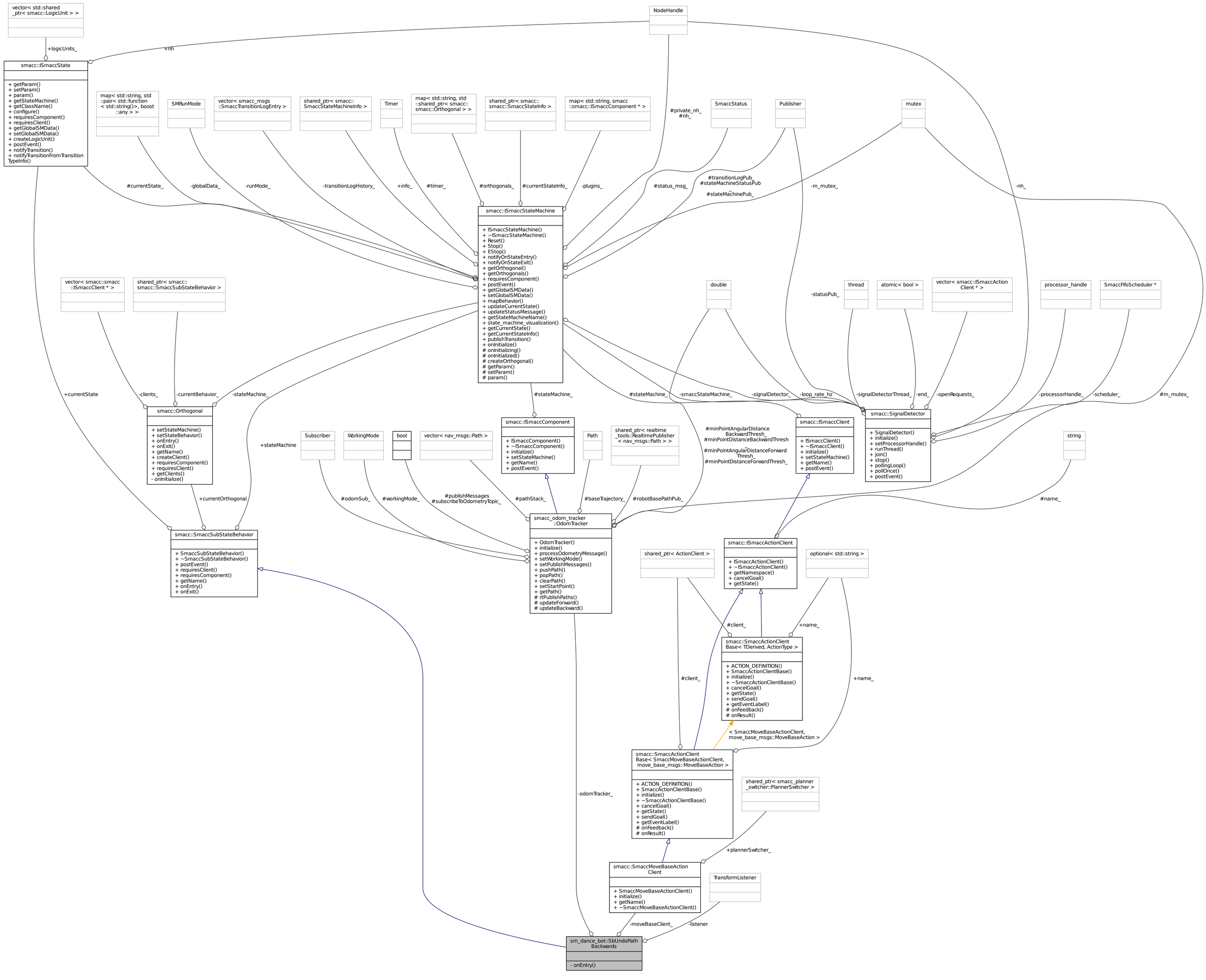
vector< std::shared _ptr< smacc::LogicUnit > >
+logicUnits_
NodeHandle
+nh
smacc::ISmaccState
+ getParam()
+ setParam()
+ param()
+ getStateMachine()
+ getClassName()
+ configure()
+ requiresComponent()
+ requiresClient()
+ getGlobalSMData()
+ setGlobalSMData()
+ createLogicUnit()
+ postEvent()
+ notifyTransition()
+ notifyTransitionFromTransition TypeInfo()
map< std::string, std ::pair< std::function < std::string()>, boost ::any > >
SMRunMode
vector< smacc_msgs ::SmaccTransitionLogEntry >
shared_ptr< smacc:: SmaccStateMachineInfo >
Timer
map< std::string, std ::shared_ptr< smacc:: smacc::Orthogonal > >
shared_ptr< smacc:: smacc::SmaccStateInfo >
map< std::string, smacc ::smacc::ISmaccComponent * >
#private_nh_ #nh_
SmaccStatus
Publisher
mutex
#currentState_
-globalData_
-runMode_
-transitionLogHistory_
+info_
#timer_
#orthogonals_
#currentStateInfo_
-plugins_
#status_msg_
#transitionLogPub_ #stateMachineStatusPub_
#stateMachinePub_
-m_mutex_
-nh_
smacc::ISmaccStateMachine
+ ISmaccStateMachine()
+ ~ISmaccStateMachine()
+ Reset()
+ Stop()
+ EStop()
+ notifyOnStateEntry()
+ notifyOnStateExit()
+ getOrthogonal()
+ getOrthogonals()
+ requiresComponent()
+ postEvent()
+ getGlobalSMData()
+ setGlobalSMData()
+ mapBehavior()
+ updateCurrentState()
+ updateStatusMessage()
+ getStateMachineName()
+ state_machine_visualization()
+ getCurrentState()
+ getCurrentStateInfo()
+ publishTransition()
+ onInitialize()
# onInitializing()
# onInitialized()
# createOrthogonal()
# getParam()
# setParam()
# param()
vector< smacc::smacc ::ISmaccClient * >
shared_ptr< smacc:: smacc::SmaccSubStateBehavior >
double
-statusPub_
thread
atomic< bool >
vector< smacc::ISmaccAction Client * >
processor_handle
SmaccFifoScheduler *
+currentState
-clients_
-currentBehavior_
-stateMachine_
#stateMachine_
#stateMachine_
-smaccStateMachine_
-signalDetector_
-loop_rate_hz
-signalDetectorThread_
-end_
-openRequests_
-processorHandle_
-scheduler_
#m_mutex_
smacc::Orthogonal
+ setStateMachine()
+ setStateBehavior()
+ onEntry()
+ onExit()
+ getName()
+ createClient()
+ requiresComponent()
+ requiresClient()
+ getClients()
- onInitialize()
smacc::ISmaccComponent
+ ISmaccComponent()
+ ~ISmaccComponent()
+ initialize()
+ setStateMachine()
+ getName()
+ postEvent()
smacc::ISmaccClient
+ ISmaccClient()
+ ~ISmaccClient()
+ initialize()
+ setStateMachine()
+ getName()
+ postEvent()
smacc::SignalDetector
+ SignalDetector()
+ initialize()
+ setProcessorHandle()
+ runThread()
+ join()
+ stop()
+ pollingLoop()
+ pollOnce()
+ postEvent()
+stateMachine
Subscriber
WorkingMode
bool
vector< nav_msgs::Path >
Path
shared_ptr< realtime _tools::RealtimePublisher < nav_msgs::Path > >
#minPointAngularDistance BackwardThresh_
#minPointDistanceBackwardThresh
#minPointAngularDistanceForward Thresh_
#minPointDistanceForwardThresh_
string
+currentOrthogonal
#odomSub_
#workingMode_
#publishMessages #subscribeToOdometryTopic_
#pathStack_
#baseTrajectory_
#robotBasePathPub_
#name_
smacc::SmaccSubStateBehavior
+ SmaccSubStateBehavior()
+ ~SmaccSubStateBehavior()
+ postEvent()
+ requiresClient()
+ requiresComponent()
+ getName()
+ onEntry()
+ onExit()
smacc_odom_tracker ::OdomTracker
+ OdomTracker()
+ initialize()
+ processOdometryMessage()
+ setWorkingMode()
+ setPublishMessages()
+ pushPath()
+ popPath()
+ clearPath()
+ setStartPoint()
+ getPath()
# rtPublishPaths()
# updateForward()
# updateBackward()
smacc::ISmaccActionClient
+ ISmaccActionClient()
+ ~ISmaccActionClient()
+ getNamespace()
+ cancelGoal()
+ getState()
shared_ptr< ActionClient >
optional< std::string >
#client_
+name_
smacc::SmaccActionClient Base< TDerived, ActionType >
+ ACTION_DEFINITION()
+ SmaccActionClientBase()
+ initialize()
+ ~SmaccActionClientBase()
+ cancelGoal()
+ getState()
+ sendGoal()
+ getEventLabel()
# onFeedback()
# onResult()
#client_
+name_
< SmaccMoveBaseActionClient, move_base_msgs::MoveBaseAction >
smacc::SmaccActionClient Base< SmaccMoveBaseActionClient, move_base_msgs::MoveBaseAction >
+ ACTION_DEFINITION()
+ SmaccActionClientBase()
+ initialize()
+ ~SmaccActionClientBase()
+ cancelGoal()
+ getState()
+ sendGoal()
+ getEventLabel()
# onFeedback()
# onResult()
-odomTracker_
shared_ptr< smacc_planner _switcher::PlannerSwitcher >
+plannerSwitcher_
smacc::SmaccMoveBaseAction Client
+ SmaccMoveBaseActionClient()
+ initialize()
+ getName()
+ ~SmaccMoveBaseActionClient()
TransformListener
-moveBaseClient_
-listener
sm_dance_bot::SbUndoPath Backwards
- onEntry()