File: communication\_node.cpp

Author: Bill Johnson

Documentation Author: Andrew Burroughs

Detailed Description:

Issues:

Software Documentation

Global Variables

**std\_msgs::msg::Empty empty**

Description of variable

**bool silentRunning**

Description of variable

**int new\_socket**

Description of variable

**rclcpp::Node::SharedPtr nodeHandle**

Description of variable

**std::string robotName**

Description of variable

**bool broadcast**

Description of variable

Function Documentation

**Function\_name**(parameters):

Description of function

Expected Input, Range(s) of Input

Expected Outputs / Results, Range

If the function returns a result, use Outputs. If the function performs some operations, but does not return a value, use Results.

**void insert**(float value, uint8\_t\* array):

Description of function

Expected Input, Range(s) of Input

Expected Outputs / Results, Range

**void insert**(int value, uint8\_t\* array):

Description of function

Expected Input, Range(s) of Input

Expected Outputs / Results, Range

**float parseFloat**(uint8\_t\* array):

Description of function

Expected Input, Range(s) of Input

Expected Outputs / Results, Range

**int parseInt**(uint8\_t\* array):

Description of function

Expected Input, Range(s) of Input

Expected Outputs / Results, Range

**void send**(BinaryMessage message):

Description of function

Expected Input, Range(s) of Input

Expected Outputs / Results, Range

**void send**(std::string messageLabel, const messages::msg::VictorOut::SharedPtr victorOut):

Description of function

Expected Input, Range(s) of Input

Expected Outputs / Results, Range

**void send**(std::string messageLabel, const messages::msg::TalonOut::SharedPtr talonOut):

Description of function

Expected Input, Range(s) of Input

Expected Outputs / Results, Range

**void send**(std::string messageLabel, const messages::msg::Power::SharedPtr power):

Description of function

Expected Input, Range(s) of Input

Expected Outputs / Results, Range

**void zedPositionCallback**(const messages::msg::ZedPosition::SharedPtr zedPosition):

Description of function

Expected Input, Range(s) of Input

Expected Outputs / Results, Range

**void powerCallback**(const messages::msg::Power::SharedPtr power):

Description of function

Expected Input, Range(s) of Input

Expected Outputs / Results, Range

**void talon1Callback**(const messages::msg::TalonOut::SharedPtr talonOut):

Description of function

Expected Input, Range(s) of Input

Expected Outputs / Results, Range

**void talon2Callback**(const messages::msg::TalonOut::SharedPtr talonOut):

Description of function

Expected Input, Range(s) of Input

Expected Outputs / Results, Range

**void talon3Callback**(const messages::msg::TalonOut::SharedPtr talonOut):

Description of function

Expected Input, Range(s) of Input

Expected Outputs / Results, Range

**void talon4Callback**(const messages::msg::TalonOut::SharedPtr talonOut):

Description of function

Expected Input, Range(s) of Input

Expected Outputs / Results, Range

**void zedImageCallback**(const sensor\_msgs::msg::Image::SharedPtr inputImage):

Description of function

Expected Input, Range(s) of Input

Expected Outputs / Results, Range

**std::string getAddressString**(int family, std::string interfaceName):

Description of function

Expected Input, Range(s) of Input

Expected Outputs / Results, Range

**Function\_name**(parameters):

Description of function

Expected Input, Range(s) of Input

Expected Outputs / Results, Range

**void printAddresses**():

Description of function

Expected Input, Range(s) of Input

Expected Outputs / Results, Range

**void reboot**():

Description of function

Expected Input, Range(s) of Input

Expected Outputs / Results, Range

**void broadcastIP**():

Description of function

Expected Input, Range(s) of Input

Expected Outputs / Results, Range

Change Log:

7/3/2022: Documentation was created