模式: 全部
左边文件: G:\ros1111111\aoa_ros\include\aoa_ros.h   右边文件: G:\aoa_ros\include\aoa_ros.h

	左			右
1	`#ifndef __AOA_ROS_H_`	=	1	`#ifndef __AOA_ROS_H_`
2	`#define __AOA_ROS_H_`		2	`#define __AOA_ROS_H_`
3			3	
4	`#include "std_msgs/Int32MultiArray.h"`	<>	4	`#include "std_msgs/msg/int32_multi_arr` `» ay.hpp"`
5	`#include <serial/serial.h>`	=	5	`#include <serial/serial.h>`
		<>	6	`#include "rclcpp/rclcpp.hpp"`
6	`#include "ros/ros.h"`		7	`#include "rclcpp/logger.hpp"`
7	`#include <geometry_msgs/PointStamped.h` `» >`			
8		=	8	
9	`#define PROTOBUFLENGHT      19`		9	`#define PROTOBUFLENGHT      19`
		-+	10	
			11	`using namespace rclcpp;`
10		=	12	
11	`#pragma pack(1)`		13	`#pragma pack(1)`
12			14	
13	`__attribute__((aligned(1))) typedef st` `» ruct`		15	`__attribute__((aligned(1))) typedef st` `» ruct`
14	`{`		16	`{`
15	`    uint16_t  crc16;`		17	`    uint16_t  crc16;`
16	`    uint8_t   end;`		18	`    uint8_t   end;`
17	`}frame_end_t;`		19	`}frame_end_t;`
18			20	
19	`__attribute__((aligned(1))) typedef st` `» ruct`		21	`__attribute__((aligned(1))) typedef st` `» ruct`
20	`{`		22	`{`
21	`    uint8_t  start;`		23	`    uint8_t  start;`
22	`    uint8_t  len;`		24	`    uint8_t  len;`
23	`}frame_title_t;`		25	`}frame_title_t;`
24			26	
25	`__attribute__((aligned(1)))  typedef s` `» truct`		27	`__attribute__((aligned(1)))  typedef s` `» truct`
26	`{`		28	`{`
27	`    frame_title_t title;//帧头`		29	`    frame_title_t title;//帧头`
28	`    uint8_t type;`		30	`    uint8_t type;`
29	`    uint8_t seq_num;//帧序号 0~255`		31	`    uint8_t seq_num;//帧序号 0~255`
30	`    int8_t rx_rssi_first;//保留`		32	`    int8_t rx_rssi_first;//保留`
31	`    int8_t rx_rssi_all;//保留`		33	`    int8_t rx_rssi_all;//保留`
32	`    int8_t   battery;//电量`		34	`    int8_t   battery;//电量`
33	`    uint8_t  keys;//按键值`		35	`    uint8_t  keys;//按键值`
34	`    uint16_t Tag_ID;//标签ID`		36	`    uint16_t Tag_ID;//标签ID`
35	`    uint16_t dist;//距离 单位 cm`		37	`    uint16_t dist;//距离 单位 cm`
36	`    int16_t  angle;//乘以 1000 以后的` `» 弧度`		38	`    int16_t  angle;//乘以 1000 以后的` `» 弧度`
37	`    uint8_t  anchor_status;//基站的状` `» 态`		39	`    uint8_t  anchor_status;//基站的状` `» 态`
38	`    uint8_t  quality;//信号质量 1质量` `» 差 0质量好`		40	`    uint8_t  quality;//信号质量 1质量` `» 差 0质量好`
39	`    frame_end_t  end;//帧尾`		41	`    frame_end_t  end;//帧尾`
40	`}AOA_report_t;`		42	`}AOA_report_t;`
41			43	
42			44	
43	`typedef union AOA_Serial_Data_Union`		45	`typedef union AOA_Serial_Data_Union`
44	`{`		46	`{`
45	`    unsigned char buffer[PROTOBUFLENGH` `» T];`		47	`    unsigned char buffer[PROTOBUFLENGH` `» T];`

46		48	
47	`    AOA_report_t AOA_report_date;`	49	`    AOA_report_t AOA_report_date;`
48		50	
49	`}AOA_Serial_Data_Union;`	51	`}AOA_Serial_Data_Union;`
50		52	
51		53	
52		54	
53	`#pragma pack(4)`	55	`#pragma pack(4)`
54		56	
55		57	
56	`using namespace std;`	58	`using namespace std;`
57		59	
58	`class AOA_ros`	60	`class AOA_ros`
59	`{`	61	`{`
60	`public:`	62	`public:`
61	`    AOA_ros();`	63	`    AOA_ros();`
62	`    ~AOA_ros();`	64	`    ~AOA_ros();`
63		65	
64	`    /* Read/Write data from ttyUSB */`	66	`    /* Read/Write data from ttyUSB */`
65	`    bool ReadFromUart(void);`	67	`    bool ReadFromUart(void);`
66	`    bool WriteToUart(unsigned char*);`	68	`    bool WriteToUart(unsigned char*);`
67	`    bool LoopProcess(void);`	69	`    bool LoopProcess(void);`
68	`    bool OpenSerial(void);`	70	`    bool OpenSerial(void);`
69		71	
70	`    //bool`	72	`    //bool`
71		73	
72	`    serial::Serial m_Robot_Serial; //` `» 声明串口对象`	74	`    serial::Serial m_Robot_Serial; //` `» 声明串口对象`
73	`    string m_strUsart_ports;`	75	`    string m_strUsart_ports;`
74	`    int m_nBaud_rate;`	76	`    int m_nBaud_rate;`

75		+-	
76		=	77	
77	`private:`	<>	78	`private:`
78	`    ros::NodeHandle m_hNodeAOA;`		79	`    shared_ptr<Node> m_hNodeAOA;`
79	`    ros::Publisher m_pAOA_pub;`		80	`    Publisher<std_msgs::msg::Int32Mult` `» iArray>::SharedPtr m_pAOA_pub;`
80	`};`	=	81	`};`
81			82	
82			83	
83	`#endif`		84	`#endif`