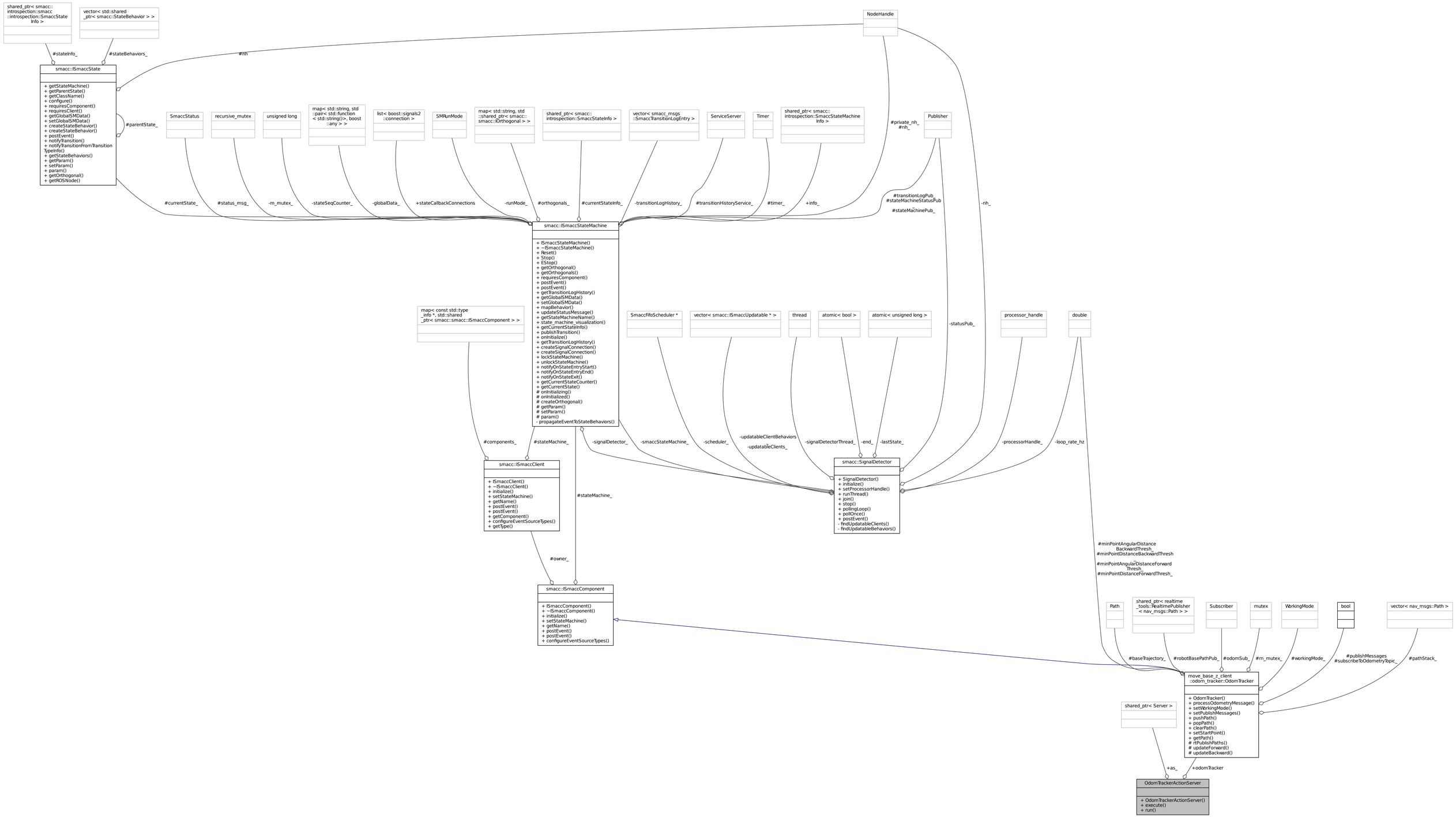
shared_ptr< smacc::introspection::smacc::introspection::SmaccStateInfo >
vector< std::shared_ptr< smacc::StateBehavior > >
NodeHandle
#stateInfo_
#stateBehaviors_
#nh
smacc::ISmaccState
+ getStateMachine()
+ getParentState()
+ getClassName()
+ configure()
+ requiresComponent()
+ requiresClient()
+ getGlobalSMData()
+ setGlobalSMData()
+ createStateBehavior()
+ createStateBehavior()
+ postEvent()
+ notifyTransition()
+ notifyTransitionFromTransitionTypeInfo()
+ getStateBehaviors()
+ getParam()
+ setParam()
+ param()
+ getOrthogonal()
+ getROSNode()
#parentState_
SmaccStatus
recursive_mutex
unsigned long
map< std::string, std::pair< std::function< std::string()>, boost::any > >
list< boost::signals2::connection >
SMRunMode
map< std::string, std::shared_ptr< smacc::IOrthogonal > >
shared_ptr< smacc::introspection::SmaccStateInfo >
vector< smacc_msgs::SmaccTransitionLogEntry >
ServiceServer
Timer
shared_ptr< smacc::introspection::SmaccStateMachineInfo >
Publisher
#private_nh_
#nh_
#currentState_
#status_msg_
-m_mutex_
-stateSeqCounter_
-globalData_
+stateCallbackConnections
-runMode_
#orthogonals_
#currentStateInfo_
-transitionLogHistory_
#transitionHistoryService_
#timer_
+info_
#transitionLogPub
#stateMachineStatusPub
#stateMachinePub_
-nh_
smacc::ISmaccStateMachine
+ ISmaccStateMachine()
+ ~ISmaccStateMachine()
+ Reset()
+ Stop()
+ EStop()
+ getOrthogonal()
+ getOrthogonals()
+ requiresComponent()
+ postEvent()
+ postEvent()
+ getTransitionLogHistory()
+ getGlobalSMData()
+ setGlobalSMData()
+ mapBehavior()
+ updateStatusMessage()
+ getStateMachineName()
+ state_machine_visualization()
+ getCurrentStateInfo()
+ publishTransition()
+ onInitialize()
+ getTransitionLogHistory()
+ createSignalConnection()
+ createSignalConnection()
+ lockStateMachine()
+ unlockStateMachine()
+ notifyOnStateEntryStart()
+ notifyOnStateEntryEnd()
+ notifyOnStateExit()
+ getCurrentStateCounter()
+ getCurrentState()
# onInitializing()
# onInitialized()
# createOrthogonal()
# getParam()
# setParam()
# param()
- propagateEventToStateBehaviors()
map< const std::type_info *, std::shared_ptr< smacc::smacc::ISmaccComponent > >
SmaccFifoScheduler *
vector< smacc::ISmaccUpdatable * >
thread
atomic< bool >
atomic< unsigned long >
-statusPub_
processor_handle
double
#components_
#stateMachine_
-signalDetector_
-smaccStateMachine_
-scheduler_
-updatableClientBehaviors
-updatableClients_
-signalDetectorThread_
-end_
-lastState_
-processorHandle_
-loop_rate_hz
smacc::ISmaccClient
+ ISmaccClient()
+ ~ISmaccClient()
+ initialize()
+ setStateMachine()
+ getName()
+ postEvent()
+ postEvent()
+ getComponent()
+ configureEventSourceTypes()
+ getType()
smacc::SignalDetector
+ SignalDetector()
+ initialize()
+ setProcessorHandle()
+ runThread()
+ join()
+ stop()
+ pollingLoop()
+ pollOnce()
+ postEvent()
- findUpdatableClients()
- findUpdatableBehaviors()
#stateMachine_
#owner_
#minPointAngularDistance_BackwardThresh_
#minPointDistanceBackwardThresh
#minPointAngularDistanceForwardThresh_
#minPointDistanceForwardThresh_
smacc::ISmaccComponent
+ ISmaccComponent()
+ ~ISmaccComponent()
+ initialize()
+ setStateMachine()
+ getName()
+ postEvent()
+ postEvent()
+ configureEventSourceTypes()
Path
shared_ptr< realtime_tools::RealtimePublisher < nav_msgs::Path > >
Subscriber
mutex
WorkingMode
bool
vector< nav_msgs::Path >
#baseTrajectory_
#robotBasePathPub_
#odomSub_
#m_mutex_
#workingMode_
#publishMessages
#subscribeToOdometryTopic_
#pathStack_
move_base_z_client::odom_tracker::OdomTracker
+ OdomTracker()
+ processOdometryMessage()
+ setWorkingMode()
+ setPublishMessages()
+ pushPath()
+ popPath()
+ clearPath()
+ setStartPoint()
+ getPath()
# rtPublishPaths()
# updateForward()
# updateBackward()
shared_ptr< Server >
+as_
+odomTracker
OdomTrackerActionServer
+ OdomTrackerActionServer()
+ execute()
+ run()