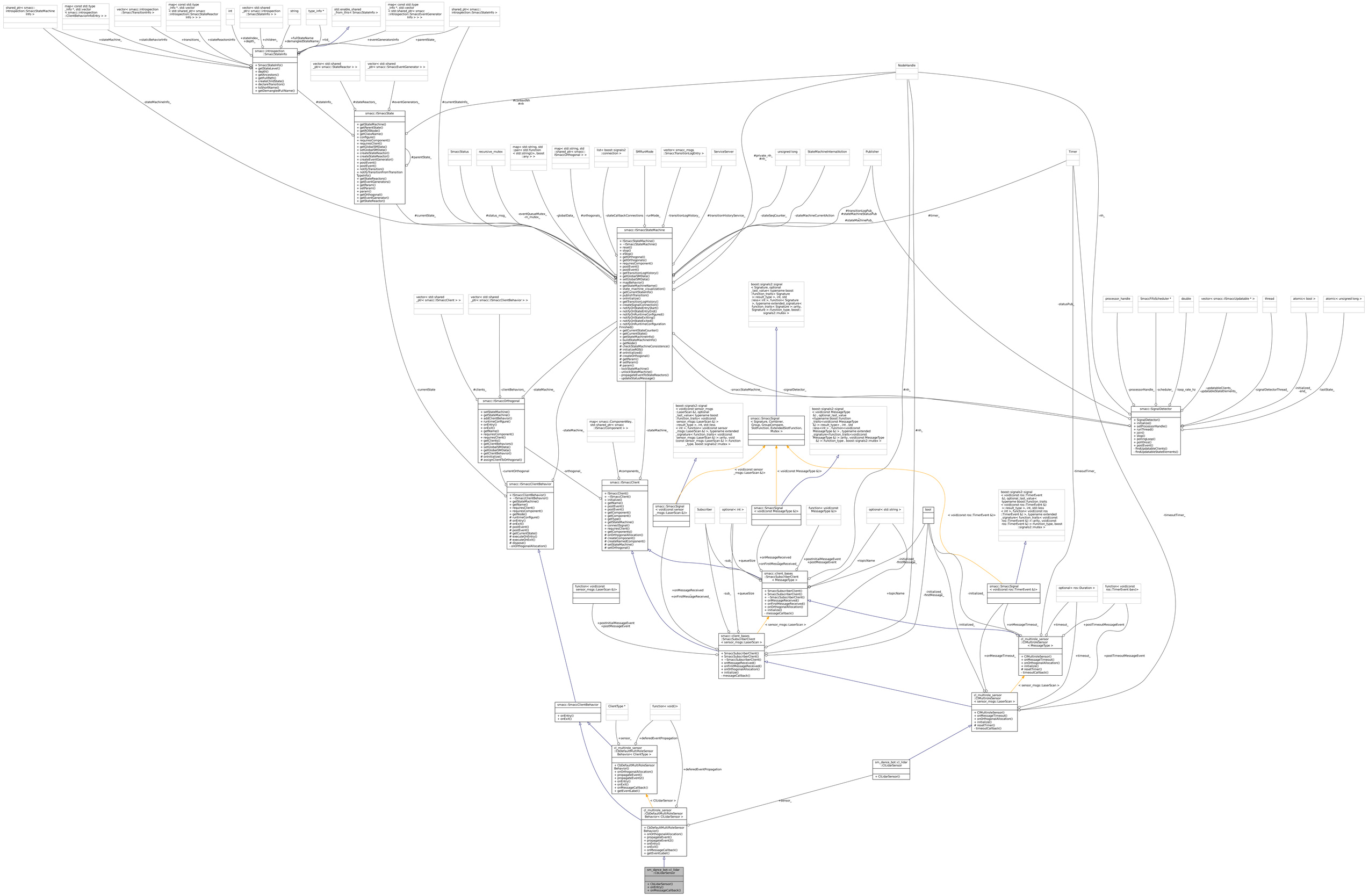
shared_ptr< smacc::introspection::SmaccStateMachineInfo >
map< const std::type_info *, std::vector< std::shared_ptr< smacc::introspection::ClientBehaviorInfoEntry > >
vector< smacc::introspection::SmaccTransitionInfo >
map< const std::type_info *, std::vector< std::shared_ptr< smacc::introspection::SmaccStateReactorInfo > > >
int
vector< std::shared_ptr< smacc::introspection::SmaccStateInfo > >
string
type_info *
std::enable_shared_from_this< SmaccStateInfo >
map< const std::type_info *, std::vector< std::shared_ptr< smacc::introspection::SmaccEventGeneratorInfo > > >
shared_ptr< smacc::introspection::SmaccStateInfo >
+stateMachine_
+staticBehaviorInfo
+transitions_
+stateReactorsInfo
+stateIndex_
+depth_
+children_
+fullStateName
+demangledStateName
+id_
+eventGeneratorsInfo
+parentState_
smacc::introspection::SmaccStateInfo
+ SmaccStateInfo()
+ getStateLevel()
+ depth()
+ getAncestors()
+ getFullPath()
+ createChildState()
+ getStateDescription()
+ toShortName()
+ getDemangledFullName()
vector< std::shared_ptr< smacc::StateReactor > >
vector< std::shared_ptr< smacc::SmaccEventGenerator > >
-stateMachineInfo_
#stateInfo_
#stateReactors_
#eventGenerators_
#currentStateInfo_
NodeHandle
#contextNh
#nh
smacc::ISmaccState
+ getStateMachine()
+ getParentState()
+ getROSNode()
+ getClassName()
+ getClass()
+ requiresComponent()
+ requiresClient()
+ getGlobalSMData()
+ setGlobalSMData()
+ getStateReactor()
+ createStateReactor()
+ getEventGenerator()
+ postEvent()
+ postEvent()
+ notifyTransition()
+ notifyTransitionFromTransitionTypeInfo()
+ getStateReactors()
+ getEventGenerators()
+ getParam()
+ setParam()
+ param()
+ getOrthogonal()
+ getEventGenerator()
+ getStateReactor()
#parentState_
SmaccStatus
recursive_mutex
map< std::string, std::pair< std::function< void(std::string)>, boost::any > >
map< std::string, std::shared_ptr< smacc::ISmaccOrthogonal > >
list< boost::signals2::connection >
SMRunMode
vector< smacc_msgs::SmaccTransitionLogEntry >
ServiceServer
#private_rh_
#nh_
unsigned long
StateMachineInternalAction
Publisher
Timer
#currentState_
#status_msg_
-eventQueueMutex_
-m_mutex_
-globalData_
#orthogonals_
-stateCallbackConnections
-runMode_
-transitionLogHistory_
#transitionHistoryService_
-stateSeqCounter_
-stateMachineCurrentAction
#transitionLogPub
#stateMachineStatusPub
#stateMachinePub_
#timer_
-rh_
smacc::ISmaccStateMachine
+ ISmaccStateMachine()
+ ~ISmaccStateMachine()
+ reset()
+ stop()
+ exit()
+ getOrthogonal()
+ getOrthogonals()
+ requiresComponent()
+ postEvent()
+ postEvent()
+ getTransitionLogHistory()
+ getGlobalSMData()
+ setGlobalSMData()
+ mapBehavior()
+ getStateMachineName()
+ state_machine_visualization()
+ getCurrentStateInfo()
+ getStateMachine()
+ onInitialized()
+ getTransitionLogHistory()
+ CreateSignalConnection()
+ notifyOnStateEntryStart()
+ notifyOnStateEntryEnd()
+ notifyOnRuntimeConfigured()
+ notifyOnStateExiting()
+ notifyOnStateExited()
+ notifyOnRuntimeConfigurationFinished()
+ getCurrentStateCounter()
+ getCurrentState()
+ getStateMachineInfo()
+ getStateMachineInfo()
+ getNode()
# checkStateMachineConsistence()
# initializeROS()
# onInitialized()
# createOrthogonal()
# getParam()
# getParam()
# param()
- lockStateMachine()
- unlockStateMachine()
- propagateEventToStateReactors()
- updateStatusMessage()
boost::signals2::signal< void(const boost::system::error_code &, std::shared_ptr< boost::asio::steady_timer >)>
vector< std::shared_ptr< smacc::ISmaccClient > >
vector< std::shared_ptr< smacc::ISmaccClientBehavior > >
processor_handle
SmaccFifoScheduler *
double
vector< smacc::ISmaccUpdatable * >
thread
atomic< bool >
atomic< unsigned long >
-currentState
#clients_
-clientBehaviors_
-stateMachine_
-smaccStateMachine_
-signalDetector_
#nh_
-statusPub_
-processorHandle_
-scheduler_
-loop_rate_hz
-updatableClients_
-updatableStateElements_
-signalDetectorThread_
-initialized_
-end_
-lastState_
smacc::ISmaccOrthogonal
+ setStateMachine()
+ getStateMachine()
+ addClientBehavior()
+ runtimeConfigure()
+ onEntry()
+ onExit()
+ getName()
+ requiresComponent()
+ requiresClient()
+ getClients()
+ getClientBehaviors()
+ setGlobalSMData()
+ getGlobalSMData()
+ getClientBehavior()
+ oninitialize()
# assignClientToOrthogonal()
-stateMachine_
map< smacc::ComponentKey, std::shared_ptr< smacc::ISmaccComponent > >
-stateMachine_
boost::signals2::signal< void(const sensor_msgs::LaserScan &), options_type, signature_type boost::function_traits< void(const sensor_msgs::LaserScan &) >::result_type >, int, std::less< int >, function< void(const sensor_msgs::LaserScan &) >, typename extended_signature< function_traits< void(const sensor_msgs::LaserScan &) >::function_type, boost::signals2::mutex >
smacc::SmaccSignal< Signature, Combiner, Group, GroupCompare, SlotFunction, ExtendedSlotFunction, Mutex >
boost::signals2::signal< void(const MessageType &), options_type, signature_type boost::function_traits< void(const MessageType &) >::result_type >, int, std::less< int >, function< void(const MessageType &) >, typename extended_signature< function_traits< void(const MessageType &) >::arity, void(const MessageType &) >::function_type , boost::signals2::mutex >
smacc::SignalDetector
+ SignalDetector()
+ initialize()
+ setProcessorHandle()
+ spinThread()
+ pin()
+ stop()
+ pollingLoop()
+ pollOnce()
+ updateAll()
- findUpdatableClients()
- findUpdatableStateElements()
-currentOrthogonal
-orthogonal_
#components_
< void(const sensor _msgs::LaserScan &)>
< void(const MessageType &)>
-timeoutTimer_
-timeoutTimer_
smacc::ISmaccClientBehavior
+ ISmaccClientBehavior()
+ ~ISmaccClientBehavior()
+ getStateMachine()
+ getName()
+ requiresClient()
+ requiresComponent()
+ getNode()
+ runtimeConfigure()
# onEntry()
# onExit()
# postEvent()
# postEvent()
# getCurrentState()
# executeOnEntry()
# executeOnExit()
# dispose()
- onOrthogonalAllocation()
smacc::ISmaccClient
+ ISmaccClient()
+ ~ISmaccClient()
+ initialize()
+ getName()
+ postEvent()
+ getClients()
+ getComponent()
+ getComponent()
+ getType()
+ getStateMachine()
+ connectSignal()
+ getComponents()
+ oninitialize()
# onOrthogonalAllocation()
# createComponent()
# createNamedComponent()
# getStateMachine()
# setOrthogonal()
smacc::SmaccSignal< void(const sensor _msgs::LaserScan &)>
Subscriber
optional< int >
smacc::SmaccSignal< void(const MessageType &)>
function< void(const MessageType &)>
optional< std::string >
bool
< void(const ros::TimerEvent &)>
boost::signals2::signal< void(const ros::TimerEvent &, typename boost::function_traits< void(const ros::TimerEvent &) >::result_type >, int, std::less< int >, function< void(const ros::TimerEvent &) >, typename extended_signature< function_traits< void(const ros::TimerEvent &) >::arity, void(const ros::TimerEvent &) >::function_type, boost::signals2::mutex >
+onMessageReceived
+onFirstMessageReceived_
+postInitialMessageEvent
+postMessageEvent
-sub_
+queueSize
smacc::client_bases::SmaccSubscriberClient< MessageType >
+ SmaccSubscriberClient()
+ SmaccSubscriberClient()
+ ~SmaccSubscriberClient()
+ onMessageReceived()
+ onFirstMessageReceived()
+ onOrthogonalAllocation()
+ initialize()
- messageCallback()
+topicName
-initialized_
-firstMessage_
smacc::SmaccSignal< void(const ros::TimerEvent &)>
optional< ros::Duration >
function< void(const ros::TimerEvent &evt)>
function< void(const sensor_msgs::LaserScan &)>
+onMessageReceived
+onFirstMessageReceived_
-initialized_
+onMessageTimeout_
+timeout_
+postTimeoutMessageEvent
+postInitialMessageEvent
+postMessageEvent
< sensor_msgs::LaserScan >
smacc::client_bases::SmaccSubscriberClient< sensor_msgs::LaserScan >
+ SmaccSubscriberClient()
+ SmaccSubscriberClient()
+ ~SmaccSubscriberClient()
+ onMessageReceived()
+ onFirstMessageReceived()
+ onOrthogonalAllocation()
+ initialize()
- messageCallback()
cl_multirole_sensor::ClMultiroleSensor< MessageType >
+ ClMultiroleSensor()
+ onMessageTimeout()
+ onOrthogonalAllocation()
+ initialize()
# resetTimer()
- timeoutCallback()
< sensor_msgs::LaserScan >
cl_multirole_sensor::ClMultiroleSensor< sensor_msgs::LaserScan >
+ ClMultiroleSensor()
+ onMessageTimeout()
+ onOrthogonalAllocation()
+ initialize()
# resetTimer()
- timeoutCallback()
smacc::SmaccClientBehavior
+ onEntry()
+ onExit()
ClientType *
function< void()>
+sensor_
+deferredEventPropagation
cl_multirole_sensor::ClDefaultMultiRoleSensorBehavior< ClientType >
+ ClDefaultMultiRoleSensorBehavior()
+ onOrthogonalAllocation()
+ propagateEvent()
+ propagateEvent2()
+ onEntry()
+ onExit()
+ onMessageCallback()
+ getEventLabel()
< CLidarSensor >
cl_multirole_sensor::ClDefaultMultiRoleSensorBehavior< CLidarSensor >
+ ClDefaultMultiRoleSensorBehavior()
+ onOrthogonalAllocation()
+ propagateEvent()
+ propagateEvent2()
+ onEntry()
+ onExit()
+ onMessageCallback()
+ getEventLabel()
sm_dance_bot::cl_lidar::CLidarSensor
+ CLidarSensor()
+sensor_
sm_dance_bot::cl_lidar::CbLidarSensor
+ CbLidarSensor()
+ onEntry()
+ onMessageCallback()