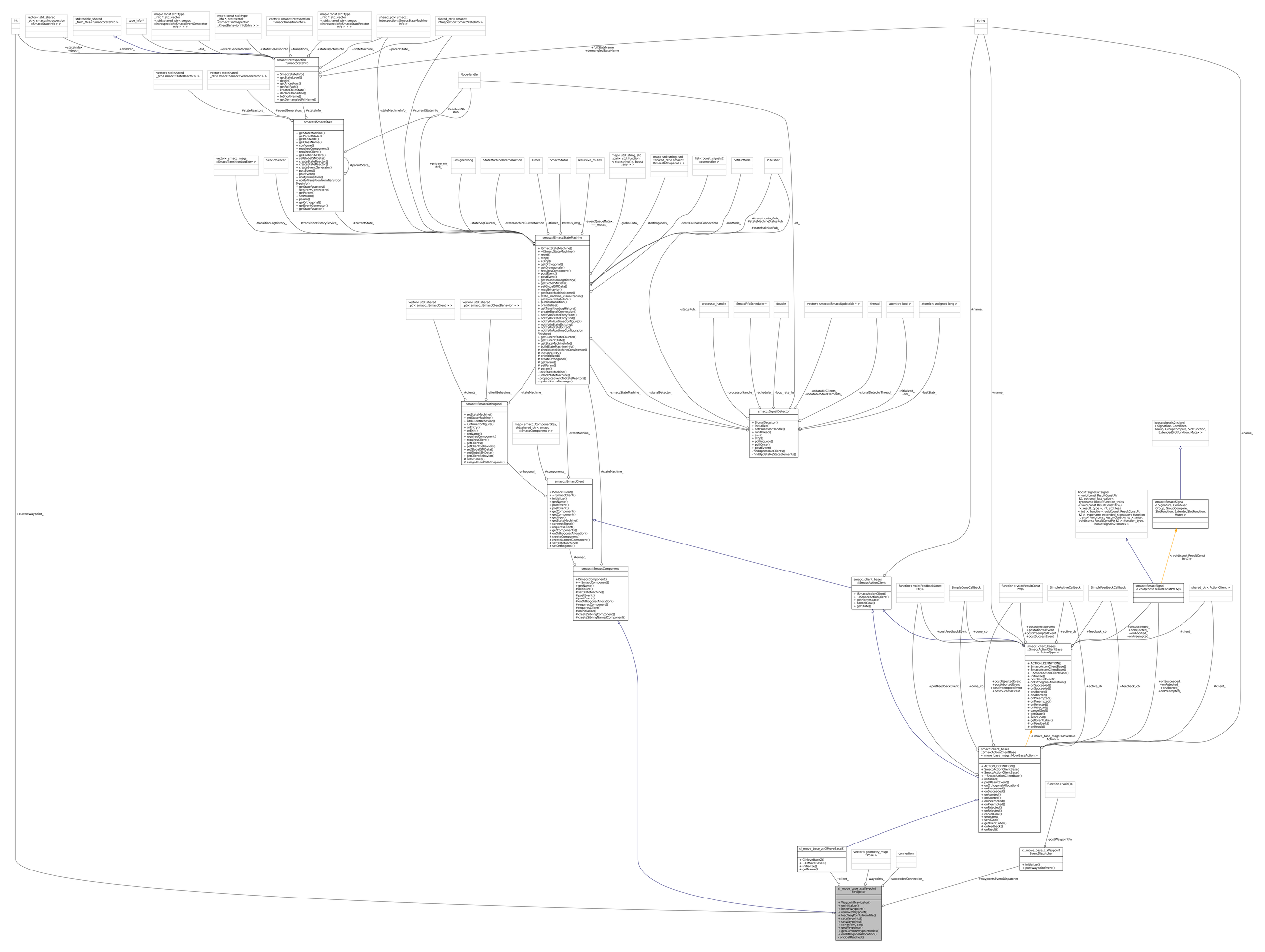
int
vector< std::shared_ptr< smacc::introspection ::SmaccStateInfo > >
std::enable_shared_from_this< SmaccStateInfo >
type_info *
map< const std::type_info *, std::vector< std::shared_ptr< smacc ::introspection::SmaccEventGenerator Info > > >
map< const std::type_info *, std::vector< smacc::introspection ::ClientBehaviorInfoEntry > >
vector< smacc::introspection ::SmaccTransitionInfo >
map< const std::type_info *, std::vector< std::shared_ptr< smacc ::introspection::SmaccStateReactor Info > > >
shared_ptr< smacc::introspection::SmaccStateMachine Info >
shared_ptr< smacc::introspection::SmaccStateInfo >
string
+stateIndex_
+depth_
+children_
+tid_
+eventGeneratorsInfo
+staticBehaviorInfo
+transitions_
+stateReactorsInfo
+stateMachine_
+parentState_
+fullStateName
+demangledStateName
smacc::introspection ::SmaccStateInfo
+ SmaccStateInfo()
+ getStateLevel()
+ depth()
+ getAncestors()
+ getFullPath()
+ createChildState()
+ declareTransition()
+ toShortName()
+ getDemangledFullName()
vector< std::shared_ptr< smacc::StateReactor > >
vector< std::shared_ptr< smacc::SmaccEventGenerator > >
#stateReactors_
#eventGenerators_
#stateInfo_
NodeHandle
-stateMachineInfo_
#currentStateInfo_
#contextNh
#nh
smacc::ISmaccState
+ getStateMachine()
+ getParentState()
+ getROSNode()
+ getClassName()
+ configure()
+ requiresComponent()
+ requiresClient()
+ getGlobalSMData()
+ setGlobalSMData()
+ createStateReactor()
+ createEventGenerator()
+ postEvent()
+ postEvent()
+ notifyTransition()
+ notifyTransitionFromTransition TypeInfo()
+ getStateReactors()
+ getEventGenerators()
+ getParam()
+ setParam()
+ param()
+ getOrthogonal()
+ getEventGenerator()
+ getStateReactor()
vector< smacc_msgs ::SmaccTransitionLogEntry >
ServiceServer
#parentState_
-transitionLogHistory_
#transitionHistoryService_
#currentState_
#private_nh_
#nh_
unsigned long
StateMachineInternalAction
Timer
SmaccStatus
recursive_mutex
map< std::string, std ::pair< std::function < std::string()>, boost ::any > >
map< std::string, std ::shared_ptr< smacc::ISmaccOrthogonal > >
list< boost::signals2 ::connection >
SMRunMode
Publisher
-stateSeqCounter_
-stateMachineCurrentAction
#timer_
#status_msg_
-eventQueueMutex_
-m_mutex_
-globalData_
#orthogonals_
-stateCallbackConnections
-runMode_
#transitionLogPub_
#stateMachineStatusPub
#stateMachinePub_
-nh_
smacc::ISmaccStateMachine
+ ISmaccStateMachine()
+ ~ISmaccStateMachine()
+ reset()
+ stop()
+ stopSM()
+ getOrthogonal()
+ getOrthogonals()
+ requiresComponent()
+ postEvent()
+ postEvent()
+ getTransitionLogHistory()
+ getGlobalSMData()
+ setGlobalSMData()
+ mapBehavior()
+ getStateMachineName()
+ state_machine_visualization()
+ publishStateMachineInfo()
+ publishTransition()
+ onInitialized()
+ getTransitionLogHistory()
+ createSignalConnection()
+ notifyOnStateEntryStart()
+ notifyOnStateEntryEnd()
+ notifyOnRuntimeConfigured()
+ notifyOnStateExitting()
+ notifyOnStateExited()
+ notifyOnRuntimeConfiguration finished()
+ getCurrentStateCounter()
+ getCurrentState()
+ getStateMachineInfo()
+ buildStateMachineInfo()
# checkStateMachineConsistence()
# initializeROS()
# onInitialized()
# createOrthogonal()
# getParam()
# setParam()
# param()
- lockStateMachine()
- unlockStateMachine()
- propagateEventToStateReactors()
- updateStatusMessage()
vector< std::shared_ptr< smacc::ISmaccClient > >
vector< std::shared_ptr< smacc::ISmaccClientBehavior > >
#clients_
-clientBehaviors_
-stateMachine_
-smaccStateMachine_
-signalDetector_
-statusPub_
processor_handle
SmaccFifoScheduler *
double
vector< smacc::ISmaccUpdatable * >
thread
atomic< bool >
atomic< unsigned long >
-processorHandle_
-scheduler_
-loop_rate_hz_
-updatableClients_
-updatableStateElements_
-signalDetectorThread_
-initialized_
-end_
-lastState_
smacc::SignalDetector
+ SignalDetector()
+ initialize()
+ setProcessorHandle()
+ runThread()
+ join()
+ stop()
+ pollingLoop()
+ pollOnce()
+ postEvent()
- findUpdatableClients()
- findUpdatableStateElements()
#name_
+name_
smacc::ISmaccOrthogonal
+ setStateMachine()
+ getStateMachine()
+ addClientBehavior()
+ runtimeConfigure()
+ onEntry()
+ onExit()
+ getName()
+ requiresComponent()
+ requiresClient()
+ getClientBehaviors()
+ setGlobalSMData()
+ getGlobalSMData()
+ getClientBehavior()
# onInitialize()
# assignClientToOrthogonal()
map< smacc::ComponentKey, std::shared_ptr< smacc ::ISmaccComponent > >
-orthogonal_
#components_
#stateMachine_
smacc::ISmaccClient
+ ISmaccClient()
+ ~ISmaccClient()
+ initialize()
+ getName()
+ postEvent()
+ postEvent()
+ getComponent()
+ getComponent()
+ getType()
+ getStateMachine()
+ connectSignal()
+ requiresClient()
+ getComponents()
# onOrthogonalAllocation()
# createComponent()
# createNamedComponent()
# setStateMachine()
# setOrthogonal()
#owner_
smacc::ISmaccComponent
+ ISmaccComponent()
+ ~ISmaccComponent()
+ getName()
# initialize()
# setStateMachine()
# postEvent()
# postEvent()
# onOrthogonalAllocation()
# requiresComponent()
# requiresClient()
# onInitialize()
# createSiblingComponent()
# createSiblingNamedComponent()
+currentWaypoint_
boost::signals2::signal< void(const ResultConstPtr &), optional_last_value< typename boost::function_traits < void(const ResultConstPtr &) >::result_type >, int, std::less< int >, function< void(const ResultConstPtr &) >, typename extended_signature< function_traits< void(const ResultConstPtr &) >::arity, void(const ResultConstPtr &) >::function_type, boost::signals2::mutex >
smacc::SmaccSignal < Signature, Combiner, Group, GroupCompare, SlotFunction, ExtendedSlotFunction, Mutex >
< void(const ResultConst Ptr &)>
smacc::client_bases ::ISmaccActionClient
+ ISmaccActionClient()
+ ~ISmaccActionClient()
+ getNamespace()
+ cancelGoal()
+ getState()
function< void(FeedbackConst Ptr)>
SimpleDoneCallback
function< void(ResultConst Ptr)>
SimpleActiveCallback
SimpleFeedbackCallback
smacc::SmaccSignal < void(const ResultConstPtr &)>
shared_ptr< ActionClient >
+postFeedbackEvent
+done_cb
+postRejectedEvent
+postAbortedEvent
+postPreemptedEvent
+postSuccessfulEvent
+active_cb
+feedback_cb
+onSucceeded_
+onRejected_
+onAborted_
+onPreempted_
#client_
smacc::client_bases ::SmaccActionClientBase < ActionType >
+ ACTION_DEFINITION()
+ SmaccActionClientBase()
+ ~SmaccActionClientBase()
+ initialize()
+ postResultEvent()
+ onOrthogonalAllocation()
+ onSucceeded()
+ onSucceeded()
+ onAborted()
+ onAborted()
+ onPreempted()
+ onPreempted()
+ onRejected()
+ onRejected()
+ cancelGoal()
+ getState()
+ sendGoal()
+ getEventLabel()
# onFeedback()
# onResult()
< move_base_msgs::MoveBase Action >
smacc::client_bases ::SmaccActionClientBase < move_base_msgs::MoveBaseAction >
+ ACTION_DEFINITION()
+ SmaccActionClientBase()
+ SmaccActionClientBase()
+ ~SmaccActionClientBase()
+ initialize()
+ postResultEvent()
+ onOrthogonalAllocation()
+ onSucceeded()
+ onSucceeded()
+ onAborted()
+ onAborted()
+ onPreempted()
+ onPreempted()
+ onRejected()
+ onRejected()
+ cancelGoal()
+ getState()
+ sendGoal()
+ getEventLabel()
# onFeedback()
# onResult()
function< void()>
-postWaypointFn
cl_move_base_z::CIMoveBaseZ
+ CIMoveBaseZ()
+ ~CIMoveBaseZ()
+ initialize()
+ getName()
vector< geometry_msgs ::Pose >
connection
+client_
-waypoints_
-succeddedConnection_
cl_move_base_z::Waypoint Navigator
+ WaypointNavigator()
+ onInitialize()
+ insertWaypoint()
+ removeWaypoint()
+ loadWayPointsFromFile()
+ setWaypoints()
+ setWaypoints()
+ clearWaypoints()
+ getWaypoints()
+ getCurrentWaypointIndex()
+ onOrthogonalAllocation()
- onGoalReached()
cl_move_base_z::Waypoint EventDispatcher
+ initialize()
+ postWaypointEvent()
+waypointsEventDispatcher