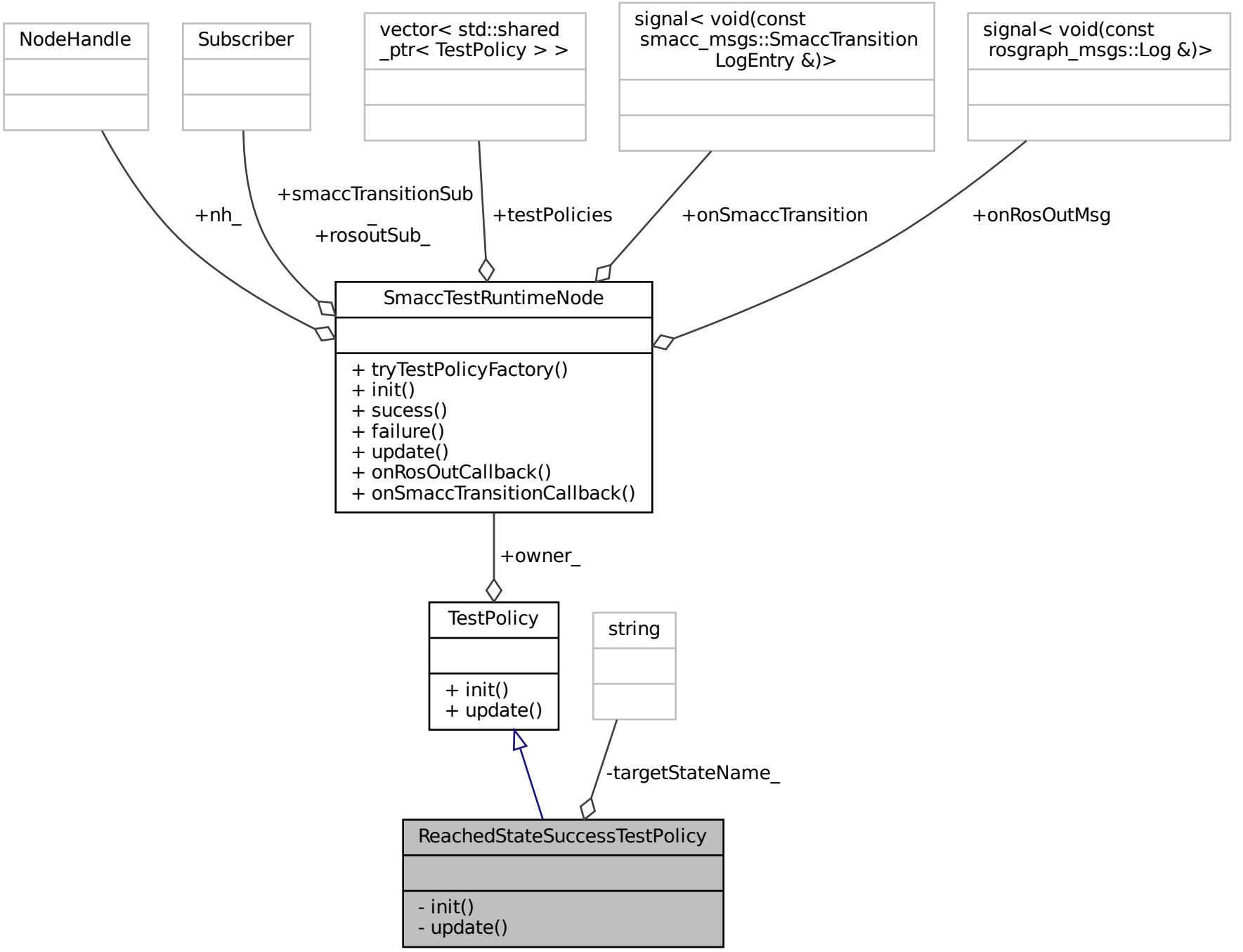
NodeHandle
Subscriber
vector< std::shared _ptr< TestPolicy > >
signal< void(const smacc_msgs::SmaccTransition LogEntry &)>
signal< void(const rosgraph_msgs::Log &)>
+nh_
+smaccTransitionSub _
+rosoutSub_
+testPolicies
+onSmaccTransition
+onRosOutMsg
SmaccTestRuntimeNode
+ tryTestPolicyFactory()
+ init()
+ sucess()
+ failure()
+ update()
+ onRosOutCallback()
+ onSmaccTransitionCallback()
+owner_
TestPolicy
+ init()
+ update()
string
-targetStateName_
ReachedStateSuccessTestPolicy
- init()
- update()