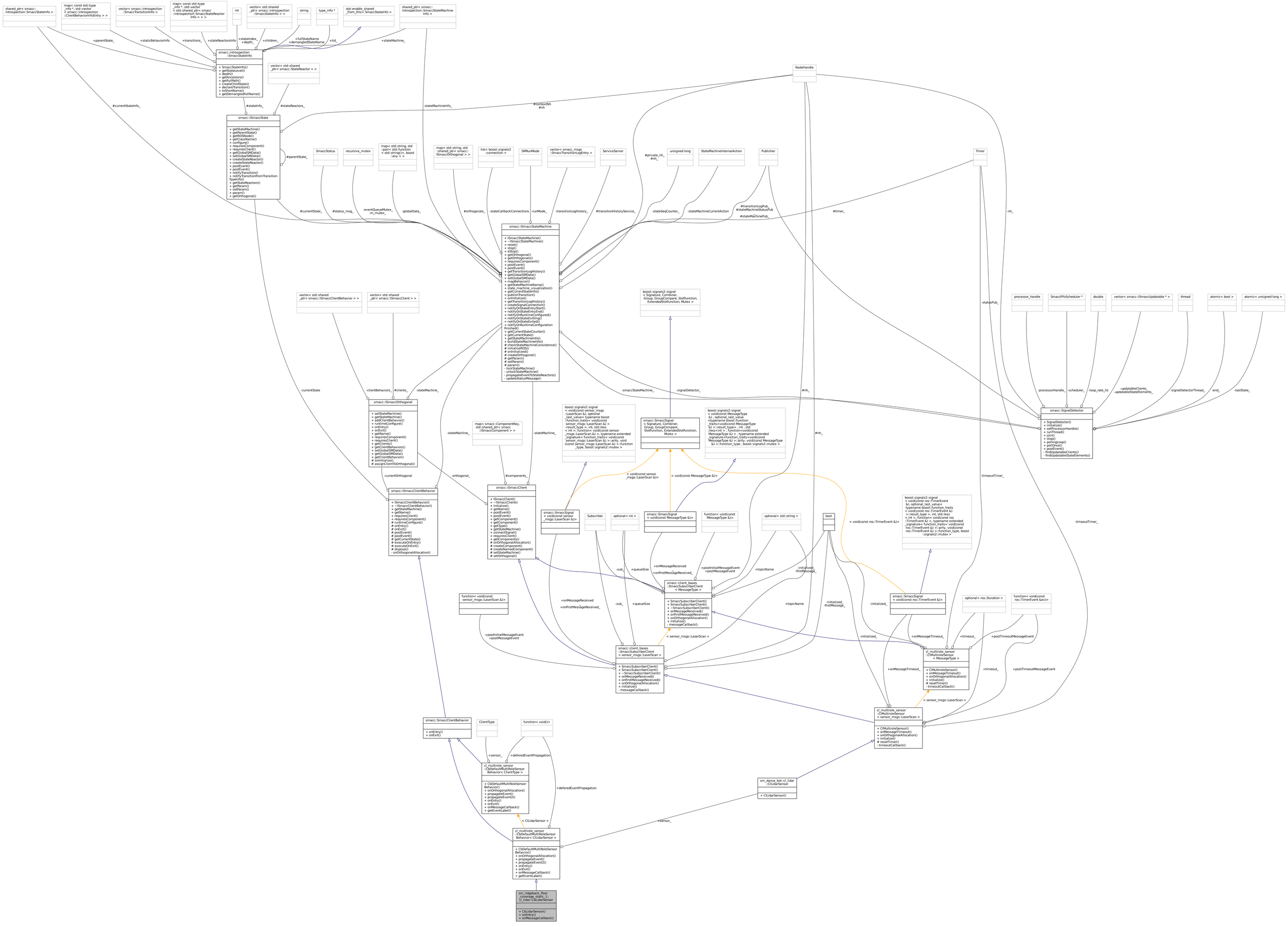
shared_ptr< smacc::introspection::SmaccStateInfo >
map< const std::type_info *, std::vector< smacc::introspection::ClientBehaviorInfoEntry > >
vector< smacc::introspection::SmaccTransitionInfo >
map< const std::type_info *, std::vector< std::shared_ptr< smacc::introspection::SmaccStateReactorInfo > > >
int
vector< std::shared_ptr< smacc::introspection::SmaccStateInfo > >
string
type_info *
std::enable_shared_from_this< SmaccStateInfo >
shared_ptr< smacc::introspection::SmaccStateMachineInfo >
+parentState_
+staticBehaviorInfo
+transitions_
+stateReactorsInfo
+stateIndex_
+depth_
+children_
+fullStateName
+demangledStateName
+tid_
+stateMachine_
smacc::introspection::SmaccStateInfo
+ SmaccStateInfo()
+ getStateLevel()
+ getTid()
+ getAncestors()
+ getFullNa()
+ createChildState()
+ declareTransition()
+ toShortName()
+ getDemangledFullName()
vector< std::shared_ptr< smacc::StateReactor > >
#currentStateInfo_
#stateInfo_
#stateReactors_
-stateMachineInfo_
#ContextNh
#nh
NodeHandle
smacc::ISmaccState
+ getStateMachine()
+ getParentState()
+ getROSNode()
+ getClassName()
+ configure()
+ requiresComponent()
+ requiresClient()
+ getGlobalSMData()
+ setGlobalSMData()
+ createStateReactor()
+ deleteStateReactor()
+ postEvent()
+ postEvent()
+ notifyTransition()
+ notifyTransitionFromTransitionTypeInfo()
+ getStateReactors()
+ getParam()
+ setParam()
+ param()
+ getOrthogonal()
#parentState_
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
vector< smacc_msgs::SmaccTransitionLogEntry >
ServiceServer
#private_nh_
#nh_
unsigned long
StateMachineInternalAction
Publisher
Timer
#currentState_
#status_msg_
-eventQueueMutex_
-nh_mutex_
-globalData_
#orthogonals_
-stateCallbackConnections
-runMode_
-transitionLogHistory_
#transitionHistoryService_
-stateSeqCounter_
-stateMachineCurrentAction
#transitionLogPub_
#stateMachineStatusPub
#stateMachinePub_
#timer_
-nh_
smacc::ISmaccStateMachine
+ ISmaccStateMachine()
+ ~ISmaccStateMachine()
+ reset()
+ stop()
+ getOrthogonal()
+ getOrthogonals()
+ requiresComponent()
+ postEvent()
+ postEvent()
+ getTransitionLogHistory()
+ getGlobalSMData()
+ setGlobalSMData()
+ mapBehavior()
+ getStateMachineName()
+ state_machine_visualization()
+ getCurrentStateInfo()
+ publishTransition()
+ onInitialized()
+ getTransitionLogHistory()
+ createSignalConnection()
+ notifyOnStateEntryStart()
+ notifyOnStateEntryEnd()
+ notifyOnRuntimeConfigured()
+ notifyOnStateExitting()
+ notifyOnStateExited()
+ notifyOnRuntimeConfiguration finished()
+ getCurrentStateCounter()
+ getCurrentState()
+ getStateMachineInfo()
+ buildStateMachineInfo()
# checkStateMachineConsistence()
# initializeROS()
# onInitialized()
# createOrthogonal()
# getParam()
# setParam()
# stop()
# ~ISmaccStateMachine()
- unlockStateMachine()
- propagateEventToStateReactors()
- updateStatusMessage()
vector< std::shared_ptr< smacc::ISmaccClientBehavior > >
vector< std::shared_ptr< smacc::ISmaccClient > >
boost::signals2::signal< Signature, Combiner, Group, GroupCompare, SlotFunction, ExtendedSlotFunction, Mutex >
processor_handle
SmaccFifoScheduler *
double
vector< smacc::ISmaccUpdatable * >
thread
atomic< bool >
atomic< unsigned long >
-statusPub_
-currentState
-clientBehaviors_
#clients_
-stateMachine_
-smaccStateMachine_
-signalDetector_
#nh_
-processorHandle_
-scheduler_
-loop_rate_hz
-updatableClients_
-updatableStateElements_
-signalDetectorThread_
-end_
-lastState_
smacc::ISmaccOrthogonal
+ getStateMachine()
+ getStateMachine()
+ addClientBehavior()
+ runtimeConfigure()
+ onEntry()
+ onExit()
+ getName()
+ requiresComponent()
+ requiresClient()
+ getClients()
+ getClientBehaviors()
+ setGlobalSMData()
+ getGlobalSMData()
+ getClientBehavior()
# onInitialize()
# assignClientToOrthogonal()
map< smacc::ComponentKey, std::shared_ptr< smacc::ISmaccComponent > >
boost::signals2::signal< void(const sensor_msgs::LaserScan &), optional_last_value< typename 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 &) >::arity, 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 &), optional_last_value< typename 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()
+ runThread()
+ join()
+ stop()
+ pollingLoop()
+ pollOnce()
+ postEvent()
- findUpdatableClients()
- findUpdatableStateElements()
-stateMachine_
-stateMachine_
-orthogonal_
#components_
-timeoutTimer_
-timeoutTimer_
-currentOrthogonal
smacc::ISmaccClientBehavior
+ ISmaccClientBehavior()
+ ~ISmaccClientBehavior()
+ getStateMachine()
+ getName()
+ requiresClient()
+ requiresComponent()
# runtimeConfigure()
# onEntry()
# onExit()
# postEvent()
# postEvent()
# getCurrentState()
# executeOnEntry()
# executeOnExit()
# dispose()
- onOrthogonalAllocation()
smacc::ISmaccClient
+ ISmaccClient()
+ ~ISmaccClient()
+ initialize()
+ getName()
+ postEvent()
+ postEvent()
+ getComponent()
+ getComponent()
+ getStateMachine()
+ connectSignal()
+ requiresClient()
+ getComponents()
# onOrthogonalAllocation()
# createComponent()
# createNamedComponent()
# setStateMachine()
# setOrthogonal()
< void(const sensor_msgs::LaserScan &)>
< void(const MessageType &)>
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 &), optional_last_value< 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 >
-sub_
+queueSize
+onMessageReceived
+onFirstMessageReceived_
+postInitialMessageEvent
+postMessageEvent
+topicName
-initialized_
-firstMessage_
smacc::client_bases::SmaccSubscriberClient< MessageType >
+ SmaccSubscriberClient()
+ SmaccSubscriberClient()
+ ~SmaccSubscriberClient()
+ onMessageReceived()
+ onFirstMessageReceived()
+ onOrthogonalAllocation()
+ initialize()
- messageCallback()
smacc::SmaccSignal< void(const ros::TimerEvent &)>
optional< ros::Duration >
function< void(const ros::TimerEvent &ev)>
function< void(const sensor_msgs::LaserScan &)>
+onMessageReceived
+onFirstMessageReceived_
-sub_
+queueSize
+topicName
-initialized_
-firstMessage_
-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::CIMultiroleSensor< MessageType >
+ CIMultiroleSensor()
+ onMessageTimeout()
+ onOrthogonalAllocation()
+ initialize()
# resetTimer()
- timeoutCallback()
+onMessageTimeout_
+timeout_
+postTimeoutMessageEvent
< sensor_msgs::LaserScan >
cl_multirole_sensor::CIMultiroleSensor< sensor_msgs::LaserScan >
+ CIMultiroleSensor()
+ onMessageTimeout()
+ onOrthogonalAllocation()
+ initialize()
# resetTimer()
- timeoutCallback()
smacc::SmaccClientBehavior
+ onEntry()
+ onExit()
ClientType
function< void()>
+sensor_
+deferedEventPropagation
cl_multirole_sensor::CbDefaultMultiRoleSensorBehavior< ClientType >
+ CbDefaultMultiRoleSensorBehavior()
+ onOrthogonalAllocation()
+ propagateEvent()
+ propagateEvent2()
+ onEntry()
+ onExit()
+ onMessageCallback()
+ getEventLabel()
+deferedEventPropagation
< CILidarSensor >
sm_dance_bot::cl_lidar::CILidarSensor
+ CILidarSensor()
+sensor_
cl_multirole_sensor::CbDefaultMultiRoleSensorBehavior< CILidarSensor >
+ CbDefaultMultiRoleSensorBehavior()
+ onOrthogonalAllocation()
+ propagateEvent()
+ propagateEvent2()
+ onEntry()
+ onExit()
+ onMessageCallback()
+ getEventLabel()
sm_ridgeback_floor_coverage_static_1::cl_lidar::CbLidarSensor
+ CbLidarSensor()
+ onEntry()
+ onMessageCallback()