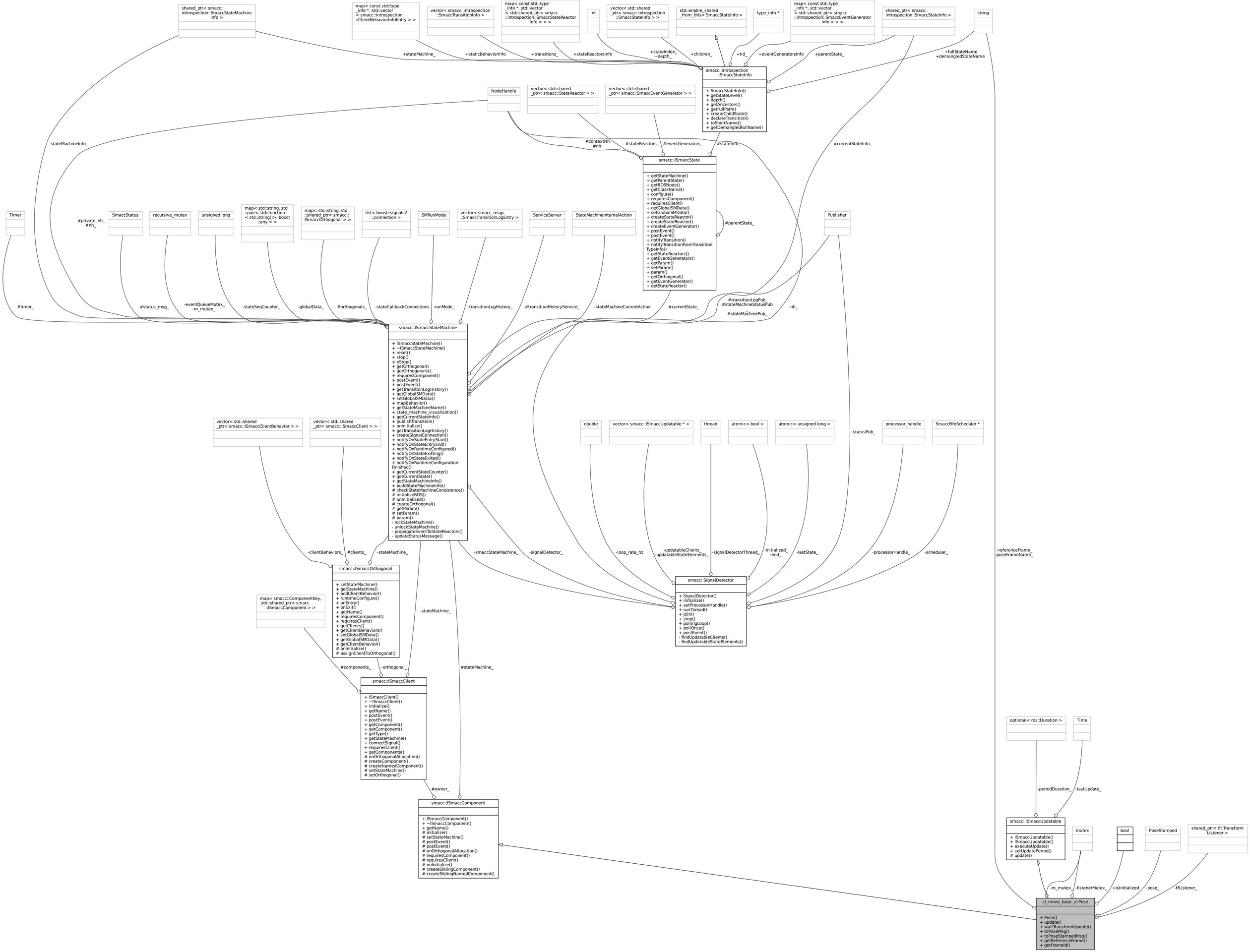
shared_ptr< smacc::
introspection::SmaccStateMachine
Info >
map< const std::type
_info *, std::vector
< smacc::introspection
::ClientBehaviorInfoEntry > >
vector< smacc::introspection
::SmaccTransitionInfo >
map< const std::type
_info *, std::vector
< std::shared_ptr< smacc
::introspection::SmaccStateReactor
Info > > >
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 > > >
shared_ptr< smacc::
introspection::SmaccStateInfo >
string
+stateMachine_
+staticBehaviorInfo
+transitions_
+stateReactorsInfo
+stateIndex_
+depth_
+children_
+tid_
+eventGeneratorsInfo
+parentState_
+fullStateName
+demangledStateName
smacc::introspection
::SmaccStateInfo
+ SmaccStateInfo()
+ getStateLevel()
+ depth()
+ getAncestors()
+ getFullPath()
+ createChildState()
+ declareTransition()
+ toShortName()
+ getDemangledFullName()
NodeHandle
vector< std::shared
_ptr< smacc::StateReactor > >
vector< std::shared
_ptr< smacc::SmaccEventGenerator > >
-stateMachineInfo_
#contextNh
#nh
#stateReactors_
#eventGenerators_
#stateInfo_
#currentStateInfo_
smacc::ISmaccState
+ getStateMachine()
+ getParentState()
+ getROSNode()
+ getClassName()
+ configure()
+ requiresComponent()
+ requiresClient()
+ getGlobalSMData()
+ setGlobalSMData()
+ createStateReactor()
+ createStateReactor()
+ createEventGenerator()
+ postEvent()
+ postEvent()
+ notifyTransition()
+ notifyTransitionFromTransition
TypeInfo()
+ getStateReactors()
+ getEventGenerators()
+ getParam()
+ setParam()
+ param()
+ getOrthogonal()
+ getEventGenerator()
+ getStateReactor()
#parentState_
Timer
#private_nh_
#nh_
SmaccStatus
recursive_mutex
unsigned long
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
StateMachineInternalAction
Publisher
#timer_
#status_msg_
-eventQueueMutex_
-m_mutex_
-stateSeqCounter_
-globalData_
#orthogonals_
-stateCallbackConnections
-runMode_
-transitionLogHistory_
#transitionHistoryService_
-stateMachineCurrentAction
#currentState_
#transitionLogPub_
#stateMachineStatusPub
#stateMachinePub_
-nh_
smacc::ISmaccStateMachine
+ ISmaccStateMachine()
+ ~ISmaccStateMachine()
+ reset()
+ stop()
+ eStop()
+ getOrthogonal()
+ getOrthogonals()
+ requiresComponent()
+ postEvent()
+ postEvent()
+ getTransitionLogHistory()
+ getGlobalSMData()
+ setGlobalSMData()
+ mapBehavior()
+ getStateMachineName()
+ state_machine_visualization()
+ getCurrentStateInfo()
+ publishTransition()
+ onInitialize()
+ getTransitionLogHistory()
+ createSignalConnection()
+ notifyOnStateEntryStart()
+ notifyOnStateEntryEnd()
+ notifyOnRuntimeConfigured()
+ notifyOnStateExiting()
+ notifyOnStateExited()
+ notifyOnRuntimeConfiguration
Finished()
+ getCurrentStateCounter()
+ getCurrentState()
+ getStateMachineInfo()
+ buildStateMachineInfo()
# checkStateMachineConsistence()
# initializeROS()
# onInitialized()
# createOrthogonal()
# getParam()
# setParam()
# param()
- lockStateMachine()
- unlockStateMachine()
- propagateEventToStateReactors()
- updateStatusMessage()
vector< std::shared
_ptr< smacc::ISmaccClientBehavior > >
vector< std::shared
_ptr< smacc::ISmaccClient > >
double
vector< smacc::ISmaccUpdatable * >
thread
atomic< bool >
atomic< unsigned long >
-statusPub_
processor_handle
SmaccFifoScheduler *
-clientBehaviors_
#clients_
-stateMachine_
-smaccStateMachine_
-signalDetector_
-loop_rate_hz
-updatableClients_
-updatableStateElements_
-signalDetectorThread_
-initialized_
-end_
-lastState_
-processorHandle_
-scheduler_
-referenceFrame_
-poseFrameName_
smacc::ISmaccOrthogonal
+ setStateMachine()
+ getStateMachine()
+ addClientBehavior()
+ runtimeConfigure()
+ onEntry()
+ onExit()
+ getName()
+ requiresComponent()
+ requiresClient()
+ getClients()
+ getClientBehaviors()
+ setGlobalSMData()
+ getGlobalSMData()
+ getClientBehavior()
# onInitialize()
# assignClientToOrthogonal()
smacc::SignalDetector
+ SignalDetector()
+ initialize()
+ setProcessorHandle()
+ runThread()
+ join()
+ stop()
+ pollingLoop()
+ pollOnce()
+ postEvent()
- findUpdatableClients()
- findUpdatableStateElements()
map< smacc::ComponentKey,
std::shared_ptr< smacc
::ISmaccComponent > >
-stateMachine_
#components_
-orthogonal_
smacc::ISmaccClient
+ ISmaccClient()
+ ~ISmaccClient()
+ initialize()
+ getName()
+ postEvent()
+ postEvent()
+ getComponent()
+ getComponent()
+ getType()
+ getStateMachine()
+ connectSignal()
+ requiresClient()
+ getComponents()
# onOrthogonalAllocation()
# createComponent()
# createNamedComponent()
# setStateMachine()
# setOrthogonal()
#stateMachine_
#owner_
smacc::ISmaccComponent
+ ISmaccComponent()
+ ~ISmaccComponent()
+ getName()
# initialize()
# setStateMachine()
# postEvent()
# postEvent()
# onOrthogonalAllocation()
# requiresComponent()
# requiresClient()
# onInitialize()
# createSiblingComponent()
# createSiblingNamedComponent()
optional< ros::Duration >
Time
-periodDuration_
-lastUpdate_
smacc::ISmaccUpdatable
+ ISmaccUpdatable()
+ ISmaccUpdatable()
+ executeUpdate()
+ setUpdatePeriod()
# update()
mutex
bool
PoseStamped
shared_ptr< tf::Transform
Listener >
-m_mutex_
-listenerMutex_
+isInitialized
-pose_
-tfListener_
cl_move_base_z::Pose
+ Pose()
+ update()
+ waitTransformUpdate()
+ toPoseMsg()
+ toPoseStampedMsg()
+ getReferenceFrame()
+ getFrameId()