type_info *
std::enable_shared_from_this< 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 > >
shared_ptr< smacc::introspection::SmaccStateInfo >
map< const std::type_info *, std::vector< std::shared_ptr< smacc::introspection::SmaccEventGeneratorInfo > > >
shared_ptr< smacc::introspection::SmaccStateMachineInfo >
string
+tid_
+staticBehaviorInfo
+transitions_
+stateReactorsInfo
+stateIndex_
+depth_
+children_
+parentState_
+eventGeneratorsInfo
+stateMachine_
+fullStateName
+demangledStateName
smacc::introspection::SmaccStateInfo
+ SmaccStateInfo()
+ getStateLevel()
+ depth()
+ getAncestors()
+ getFullPath()
+ createChildState()
+ declareTransition()
+ toShortName()
+ getDemangledFullName()
vector< std::shared_ptr< smacc::SmaccEventGenerator > >
vector< std::shared_ptr< smacc::StateReactor > >
NodeHandle
#stateInfo_
#currentStateInfo_
#eventGenerators_
#stateReactors_
#contextNh
#nh
-stateMachineInfo_
smacc::ISmaccState
+ getStateMachine()
+ getParentState()
+ getROSNode()
+ getClassName()
+ configure()
+ requiresComponent()
+ requiresClient()
+ getGlobalSMData()
+ setGlobalSMData()
+ createStateReactor()
+ createStateReactor()
+ createEventGenerator()
+ postEvent()
+ postEvent()
+ notifyTransition()
+ notifyTransitionFromTransitionTypeInfo()
+ getStateReactors()
+ getEventGenerators()
+ getParam()
+ setParam()
+ param()
+ getOrthogonal()
+ getEventGenerator()
+ getStateReactor()
#parentState_
ServiceServer
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
vector< smacc_msgs::SmaccTransitionLogEntry >
Publisher
#currentState_
#transitionHistoryService_
-stateSeqCounter_
-stateMachineCurrentAction
#timer_
#status_msg_
-eventQueueMutex_
-m_mutex_
#private_nh_
#nh_
-globalData_
#orthogonals_
-stateCallbackConnections
-runMode_
-transitionLogHistory_
#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()
+ notifyOnStateExitting()
+ notifyOnStateExited()
+ notifyOnRuntimeConfigurationFinished()
+ getCurrentStateCounter()
+ getCurrentState()
+ getStateMachineInfo()
+ buildStateMachineInfo()
+ getNode()
# checkStateMachineConsistence()
# initializeROS()
# onInitialized()
# createOrthogonal()
# getParam()
# setParam()
# param()
- lockStateMachine()
- unlockStateMachine()
- propagateEventToStateReactors()
- updateStatusMessage()
vector< std::shared_ptr< smacc::ISmaccClient > >
vector< std::shared_ptr< smacc::ISmaccClientBehavior > >
processor_handle
SmaccFifoScheduler *
vector< smacc::ISmaccUpdatable * >
thread
atomic< unsigned long >
atomic< bool >
double
-statusPub_
#name_
-currentState
#clients_
-clientBehaviors_
-stateMachine_
-smaccStateMachine_
-signalDetector_
-processorHandle_
-scheduler_
-updatableClients_
-updatableStateElements_
-signalDetectorThread_
-lastState_
-initialized_
-end_
-loop_rate_hz
+name_
#odomFrame_
-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()
boost::signals2::signal< Signature, Combiner, Group, GroupCompare, SlotFunction, ExtendedSlotFunction, Mutex >
map< smacc::ComponentKey, std::shared_ptr< smacc::ISmaccComponent > >
-stateMachine_
-currentOrthogonal
-orthogonal_
#components_
#stateMachine_
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()
+ postEvent()
+ getComponent()
+ getComponent()
+ getType()
+ getStateMachine()
+ connectSignal()
+ requiresClient()
+ getComponents()
# onOrthogonalAllocation()
# createComponent()
# createNamedComponent()
# setStateMachine()
# setOrthogonal()
boost::signals2::signal< void(), optional_last_value< typename boost::function_traits< void() >::result_type >, int, std::less< int >, function< void() >, typename extended_signature< function_traits< void() >::arity, void() >::function_type, boost::signals2::mutex >
smacc::SmaccSignal< Signature, Combiner, Group, GroupCompare, SlotFunction, ExtendedSlotFunction, Mutex >
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 >
#owner_
#visualizationMarkersPub_
#clearPointDistanceThreshold
#recordPointDistanceThreshold
#clearAngularDistanceThreshold
#recordAngularDistanceThreshold_
Time
optional< ros::Duration >
-lastUpdate_
-periodDuration_
smacc::ISmaccComponent
+ ISmaccComponent()
+ ~ISmaccComponent()
+ getName()
# initialize()
# setStateMachine()
# postEvent()
# postEvent()
# onOrthogonalAllocation()
# requiresComponent()
# requiresClient()
# onInitialize()
# createSiblingComponent()
# createSiblingNamedComponent()
smacc::ISmaccUpdatable
+ ISmaccUpdatable()
+ ISmaccUpdatable()
+ executeUpdate()
+ setUpdatePeriod()
# update()
< void()>
< void(const ResultConstPtr &)>
function< void()>
future< int >
smacc::SmaccSignal< void()>
smacc::client_bases::ISmaccActionClient
+ ISmaccActionClient()
+ ~ISmaccActionClient()
+ getNamespace()
+ cancelGoal()
+ getState()
shared_ptr< ActionClient >
SimpleDoneCallback
smacc::SmaccSignal< void(const ResultConstPtr &)>
SimpleFeedbackCallback
function< void(ResultConstPtr)>
function< void(FeedbackConstPtr)>
SimpleActiveCallback
vector< nav_msgs::Path >
CallbackType
Server< move_base_z_client_plugin::OdomTrackerConfig >
Path
shared_ptr< realtime_tools::RealtimePublisher< nav_msgs::Path > >
Subscriber
WorkingMode
bool
mutex
PoseStamped
shared_ptr< tf::TransformListener >
-postFinishEventFn_
-postSuccessEventFn_
-postFailureEventFn_
-onEntryThread_
-onExitThread_
-onFinished_
-onSuccess_
-onFailure_
#client_
+done_cb
+onSucceeded_
+onRejected_
+onAborted_
+onPreempted_
+feedback_cb
+postRejectedEvent
+postAbortedEvent
+postPreemptedEvent
+postSuccessEvent
+postFeedbackEvent
+active_cb
#pathStack_
#f
#paramServer_
#aggregatedStackPathMsg
#baseTrajectory_
#robotBasePathStackedPub
#robotBasePathPub_
#odomSub_
#workingMode_
#publishMessages
#subscribeToOdometryTopic_
+isInitialized
#m_mutex_
-listenerMutex_
-m_mutex_
-pose_
-tfListener_
smacc::SmaccAsyncClientBehavior
+ onOrthogonalAllocation()
+ ~SmaccAsyncClientBehavior()
+ onSuccess()
+ onFinished()
+ onFailure()
# executeOnEntry()
# executeOnExit()
# postSuccessEvent()
# postFailureEvent()
# dispose()
smacc::client_bases::SmaccActionClientBase< ActionType >
+ ACTION_DEFINITION()
+ SmaccActionClientBase()
+ SmaccActionClientBase()
+ ~SmaccActionClientBase()
+ initialize()
+ postResultEvent()
+ onOrthogonalAllocation()
+ onSucceeded()
+ onSucceeded()
+ onAborted()
+ onAborted()
+ onPreempted()
+ onPreempted()
+ onRejected()
+ onRejected()
+ cancelGoal()
+ getState()
+ sendGoal()
+ getEventLabel()
# onFeedback()
# onResult()
cl_move_base_z::odom_tracker::OdomTracker
+ OdomTracker()
+ processOdometryMessage()
+ setWorkingMode()
+ setPublishMessages()
+ pushPath()
+ popPath()
+ clearPath()
+ setStartPoint()
+ setStartPoint()
+ getPath()
+ logStateString()
+ getStackedPaths()
# reconfigCB()
# rtPublishPaths()
# updateRecordPath()
# updateClearPath()
# updateAggregatedStackPath()
cl_move_base_z::Pose
+ Pose()
+ update()
+ waitTransformUpdate()
+ toPoseMsg()
+ toPoseStampedMsg()
+ getReferenceFrame()
+ getFrameId()
< move_base_msgs::MoveBaseAction >
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()
-goalLinePassed_
-postVirtualLinePassed_
-odomTracker_
-robotPose_
cl_move_base_z::ClMoveBaseZ
+ ClMoveBaseZ()
+ ~ClMoveBaseZ()
+ initialize()
+ getName()
#moveBaseClient_
cl_move_base_z::CbMoveBaseClientBehaviorBase
+ onOrthogonalAllocation()
- propagateSuccessEvent()
- propagateFailureEvent()
Goal
float
TransformListener
-goal_
-triggerThreshold_
-initial_plane_side_
-listener
cl_move_base_z::CbUndoPathBackwards2
+ CbUndoPathBackwards2()
+ onEntry()
+ onExit()
+ update()
+ onOrthogonalAllocation()
- publishMarkers()
- evalPlaneSide()