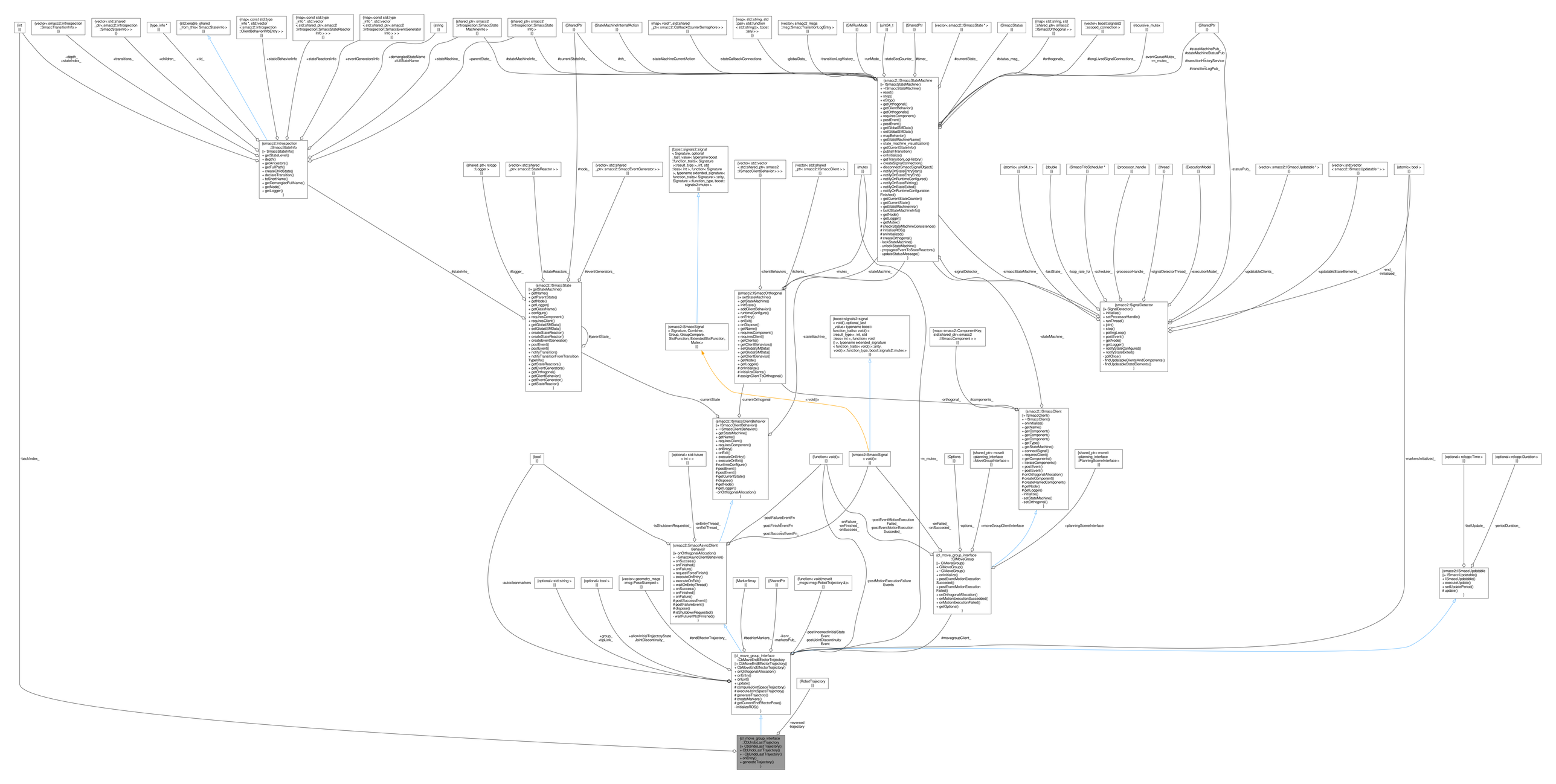
[int]
[vector< smacc2::introspection::SmaccTransitionInfo >]
[vector< std::shared_ptr< smacc2::introspection::SmaccStateInfo > >]
[type_info *]
[std::enable_shared_from_this< SmaccStateInfo >]
[map< const std::type_info *, std::vector< smacc2::introspection::ClientBehaviorInitialEntry > >]
[map< const std::type_info *, std::shared_ptr< smacc2::introspection::SmaccStateReactorInfo > >]
[map< const std::type_info *, std::shared_ptr< smacc2::introspection::SmaccEventGeneratorInfo > >]
[string]
[shared_ptr< smacc2::introspection::SmaccStateMachineInfo >]
[shared_ptr< smacc2::introspection::SmaccStateInfo >]
[SharedPtr]
[StateMachineInternalAction]
[map< void *, std::shared_ptr< smacc2::CallbackCounterSemaphore > >]
[map< std::string, std::pair< std::function < std::string()>, boost::any > >]
[vector< smacc2_msgs::msg::SmaccTransitionLogEntry >]
[ISMRunMode]
[uint64_t]
[SharedPtr]
[vector< smacc2::ISmaccState * >]
[SmaccStatus]
[map< std::string, std::shared_ptr< smacc2::ISmaccOrthogonal > >]
[vector< boost::signals2::scoped_connection >]
[recursive_mutex]
[SharedPtr]
+depth_
+stateIndex_
+transitions_
+children_
+id_
+staticBehaviorInfo
+stateReactorsInfo
+eventGeneratorsInfo
+demangledStateName
+fullStateName
+stateMachine_
+parentState_
#stateMachineInfo_
#currentStateInfo_
#rth_
-stateMachineCurrentAction
-stateCallbackConnections
-globalData_
-transitionLogHistory_
-runMode_
-stateSeqCounter_
#timer_
#currentState_
#status_msg_
#orthogonals_
#longLivedSignalConnections_
-eventQueueMutex_
-m_mutex_
#stateMachinePub_
#stateMachineStatusPub
#transitionHistoryService
#transitionLogPub_
[smacc2::ISmaccStateMachine
[|= ISmaccStateMachine()
+ ~ISmaccStateMachine()
+ reset()
+ stop()
+ eStop()
+ getOrthogonal()
+ getClientBehavior()
+ getOrthogonals()
+ requiresComponent()
+ postEvent()
+ postEvent()
+ getGlobalSMData()
+ setGlobalSMData()
+ mapBehavior()
+ getStateMachineName()
+ state_machine_visualization()
+ getCurrentStateInfo()
+ publishTransition()
+ onInitialize()
+ getTransitionLogHistory()
+ createSignalConnection()
+ disconnectSmaccSignalObject()
+ notifyOnStateEntryStart()
+ notifyOnStateEntryEnd()
+ notifyOnRuntimeConfigured()
+ notifyOnStateExiting()
+ notifyOnStateExited()
+ notifyOnRuntimeConfigurationFinished()
+ getCurrentStateCounter()
+ getCurrentState()
+ getStateMachineInfo()
+ buildStateMachineInfo()
+ getNode()
+ getLogger()
+ getMutex()
# checkStateMachineConsistence()
# initializeROS()
# onInitialized()
# createOrthogonal()
- lockStateMachine()
- unlockStateMachine()
- propagateEventToStateReactors()
- updateStatusMessage()
]
-statusPub_
[smacc2::introspection::SmaccStateInfo
[|= SmaccStateInfo()
+ getStateLevel()
+ depth()
+ getAncestors()
+ getFullPath()
+ createChildState()
+ declareTransition()
+ toShortName()
+ getDemangledFullName()
+ getNode()
+ getLogger()
]
[shared_ptr< rclcpp::Logger >]
[vector< std::shared_ptr< smacc2::StateReactor > >]
[vector< std::shared_ptr< smacc2::SmaccEventGenerator > >]
[boost::signals2::signal
< Signature, optional
_last, value= typename boost
::function_traits< Signature
>::result_type >, int, std
::less< int >, Combiner, Signature
= typename extended_signature<
function_traits< Signature >::arity,
Signature=>function_type, boost::
signals2::mutex >
]
[vector< std::vector
< std::shared_ptr< smacc2
::ISmaccClientBehavior > >
]
[vector< std::shared
_ptr< smacc2::ISmaccClient > >
]
[mutex]
[atomic< uint64_t >]
[double]
[ISmaccFifoScheduler *]
[processor_handle]
[thread]
[ExecutionModel]
[vector< smacc2::ISmaccUpdatable * >]
[vector< std::vector
< smacc2::ISmaccUpdatable * > >
]
[atomic< bool >]
#node_
#stateInfo_
#logger_
#stateReactors_
#eventGenerators_
-clientBehaviors_
#clients_
-mutex_
-stateMachine_
-signalDetector_
-smaccStateMachine_
-lastState_
-loop_rate_hz
-scheduler_
-processorHandle_
-signalDetectorThread_
-executionModel_
-updatableClients_
-updatableStateElements_
-end_
-initialized_
[smacc2::ISmaccState
[|= getStateMachine()
+ getName()
+ getParentState()
+ getNode()
+ getLogger()
+ getClassName()
+ configure()
+ requiresComponent()
+ requiresClient()
+ getGlobalSMData()
+ setGlobalSMData()
+ createStateReactor()
+ createStateReactor()
+ createEventGenerator()
+ postEvent()
+ postEvent()
+ notifyTransition()
+ notifyTransitionFromTransitionTypeInfo()
+ getStateReactors()
+ getEventGenerators()
+ getOrthogonal()
+ getClientBehavior()
+ getStateReactor()
+ getStateReactor()
]
#parentState_
[smacc2::SmaccSignal
< Signature, Combiner,
Group, GroupCompare,
SlotFunction, ExtendedSlotFunction,
Mutex >
]
[smacc2::ISmaccOrthogonal
[|= setStateMachine()
+ getStateMachine()
+ initState()
+ addClientBehavior()
+ runtimeConfigure()
+ onEntry()
+ onExit()
+ onDispose()
+ getName()
+ requiresComponents()
+ requiresClient()
+ getClients()
+ getClientBehaviors()
+ setGlobalSMData()
+ getGlobalSMData()
+ getClientBehavior()
+ getNode()
+ getLogger()
# onInitialize()
# initializeClients()
# assignClientToOrthogonal()
]
-stateMachine_
[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 >
]
[map< smacc2::ComponentKey,
std::shared_ptr< smacc2
::ISmaccComponent > >
]
-stateMachine_
[smacc2::ISmaccSignalDetector
[|= SignalDetector()
+ initialize()
+ setProcessorHandle()
+ runThread()
+ join()
+ stop()
+ pollingLoop()
+ postEvent()
+ getNode()
+ getLogger()
+ notifyStateConfigured()
+ notifyStateExited()
- pollOnce()
- findUpdatableClientsAndComponents()
- findUpdatableStateElements()
]
-currentState
-currentOrthogonal
< void()>
-orthogonal_
#components_
[smacc2::ISmaccClientBehavior
[|= ISmaccClientBehavior()
+ ~ISmaccClientBehavior()
+ getStateMachine()
+ getName()
+ requiresClient()
+ requiresComponent()
+ onEntry()
+ onExit()
+ executeOnEntry()
+ executeOnExit()
# runtimeConfigure()
# postEvent()
# postEvent()
# getCurrentState()
# dispose()
# getNode()
# getLogger()
- onOrthogonalAllocation()
]
[smacc2::ISmaccClient
[|= ISmaccClient()
+ ~ISmaccClient()
+ onInitialize()
+ getName()
+ getComponent()
+ getComponent()
+ getComponent()
+ getComponent()
+ getType()
+ getStateMachine()
+ connectSignal()
+ requiresClient()
+ getComponents()
+ iterateComponents()
+ postEvent()
+ postEvent()
# onOrthogonalAllocation()
# createComponent()
# createNamedComponent()
# getNode()
# getLogger()
- init()
- setStateMachine()
- setOrthogonal()
]
-m_mutex_
[Options]
[shared_ptr< moveit
::planning_interface
::MoveGroupInterface >
]
[shared_ptr< moveit
::planning_interface
::PlanningSceneInterface >
]
-markersInitialized_
[optional< rclcpp::Time >]
[optional< rclcpp::Duration >]
[bool]
[optional< std::future
< int > >
]
[function< void()>]
[smacc2::SmaccSignal
< void()>]
-onEntryThread_
-onExitThread_
-isShutdownRequested_
-postFailureEventFn
-postFinishEventFn
-postSuccessEventFn
-onFailure_
-onFinished_
-onSuccess_
-postEventMotionExecution
Failed_
-postEventMotionExecution
Succeded_
-onFailed_
-onSucceded_
-options_
+moveGroupClientInterface
+planningSceneInterface
[smacc2::SmaccAsyncClient
Behavior
[|= onOrthogonalAllocation()
+ ~SmaccAsyncClientBehavior()
+ onSuccess()
+ onFinished()
+ onFailure()
+ requestForceFinish()
+ executeOnEntry()
+ executeOnExit()
+ waitOnEntryThread()
+ onSuccess()
+ onFinished()
+ onFailure()
# postSuccessEvent()
# postFailureEvent()
# dispatch()
# isShutdownRequested()
- waitFutureNotFinished()
]
[cl_move_group_interface
::ClMoveGroup
[|= ClMoveGroup()
+ ClMoveGroup()
+ ~ClMoveGroup()
+ onEntry()
+ postEventMotionExecution
Succeded()
+ postEventMotionExecution
Failed()
+ onOrthogonalAllocation()
+ onMotionExecutionSucceded()
+ onMotionExecutionFailed()
+ getOptions()
]
+movegroupClient_
[ISmaccUpdatable
[|= ISmaccUpdatable()
+ ~ISmaccUpdatable()
+ execute(update())
+ setUpdatePeriod()
# update()
]
-lastUpdate_
-periodDuration_
-backIndex_
-autolearnmarkers
[optional< std::string >]
[optional< bool >]
[vector< geometry_msgs
::msg::PoseStamped >
]
[MarkerArray]
[SharedPtr]
[function< void(moveit
_msgs::msg::RobotTrajectory &)>
]
-postMotionExecutionFailure
Events
+group_
+ikLink_
+allowInitialTrajectoryState
JointDiscontinuity_
#endEffectorTrajectory_
#beahiorMarkers_
-iksrv_
-markersPub_
postIncorrectInitialState
Event
postJointDiscontinuity
Event
[cl_move_group_interface
::ClMoveEndEffectorTrajectory
[|= ClMoveEndEffectorTrajectory()
+ ~ClMoveEndEffectorTrajectory()
+ onOrthogonalAllocation()
+ onEntry()
+ onExit()
+ update()
# computeJointSpaceTrajectory()
# executeJointSpaceTrajectory()
# generateTrajectory()
# createMarkers()
# getCurrentEndEffectorPose()
- initializeROS()
]
[RobotTrajectory]
-reversed
-trajectory
[cl_move_group_interface
::ClUndoLastTrajectory
[|= ClUndoLastTrajectory()
+ ~ClUndoLastTrajectory()
+ ~~ClUndoLastTrajectory()
+ onEntry()
+ generateTrajectory()
]