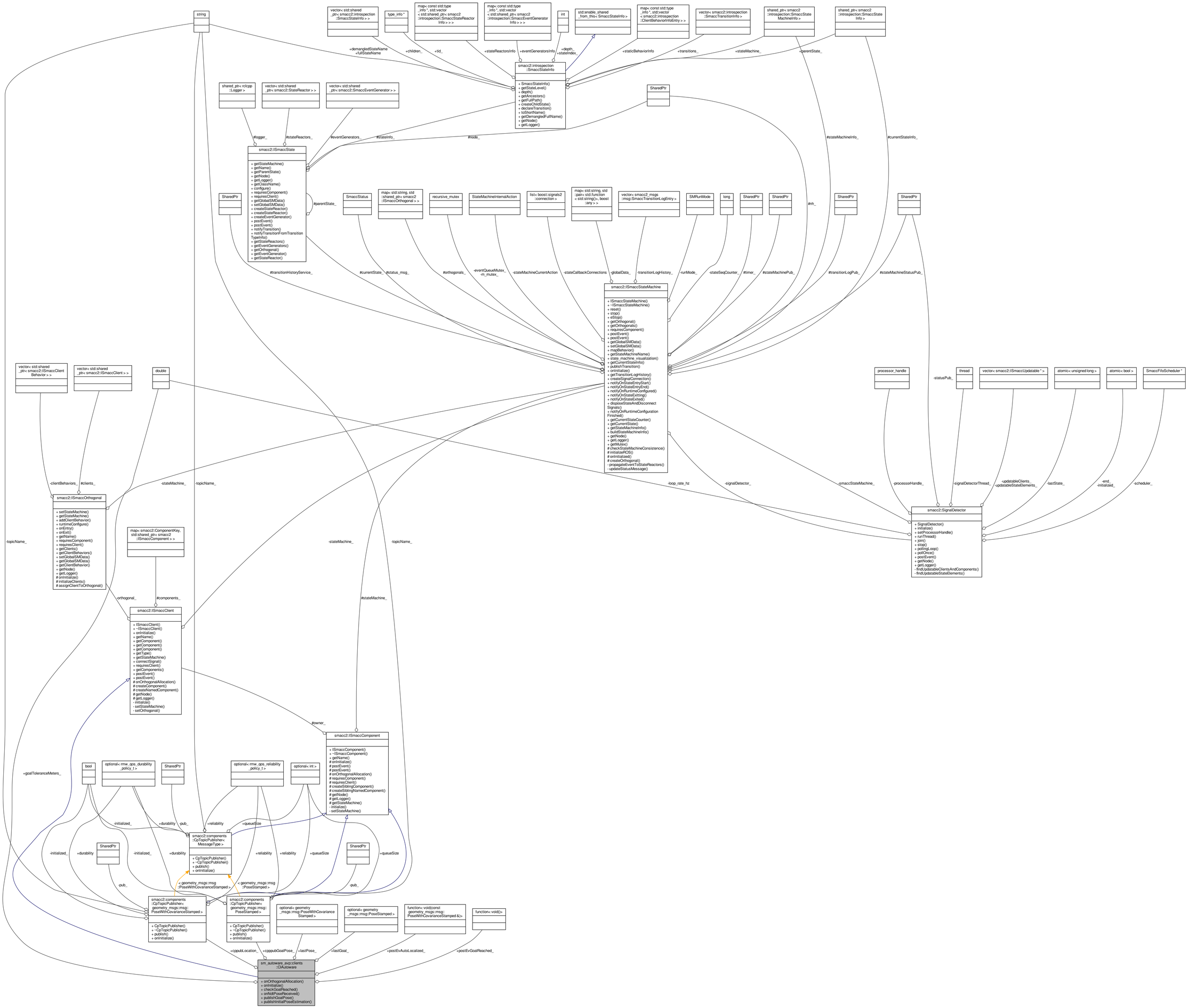
string
vector< std::shared _ptr< smacc2::introspection ::SmaccStateInfo > >
type_info *
map< const std::type _info *, std::vector < std::shared_ptr< smacc2 ::introspection::SmaccStateReactor Info > > >
map< const std::type _info *, std::vector < std::shared_ptr< smacc2 ::introspection::SmaccEventGenerator Info > > >
int
std::enable_shared _from_this< SmaccStateInfo >
map< const std::type _info *, std::vector < smacc2::introspection ::ClientBehaviorInfoEntry > >
vector< smacc2::introspection ::SmaccTransitionInfo >
shared_ptr< smacc2 ::introspection::SmaccState MachineInfo >
shared_ptr< smacc2 ::introspection::SmaccState Info >
+demangledStateName
+fullStateName
+children_
+tid_
+stateReactorsInfo
+eventGeneratorsInfo
+depth_
+stateIndex_
+staticBehaviorInfo
+transitions_
+stateMachine_
+parentState_
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 > >
SharedPtr
#logger_
#stateReactors_
#eventGenerators_
#stateInfo_
#node_
#stateMachineInfo_
#currentStateInfo_
smacc2::ISmaccState
+ getStateMachine()
+ getName()
+ getParentState()
+ getNode()
+ getLogger()
+ getClassName()
+ configure()
+ requiresComponent()
+ requiresClient()
+ getGlobalSMData()
+ setGlobalSMData()
+ createStateReactor()
+ createStateReactor()
+ createEventGenerator()
+ postEvent()
+ postEvent()
+ notifyTransition()
+ notifyTransitionFromTransition TypeInfo()
+ getStateReactors()
+ getEventGenerators()
+ getOrthogonal()
+ getEventGenerator()
+ getStateReactor()
#parentState_
SharedPtr
SmaccStatus
map< std::string, std ::shared_ptr< smacc2 ::ISmaccOrthogonal > >
recursive_mutex
StateMachineInternalAction
list< boost::signals2 ::connection >
map< std::string, std ::pair< std::function < std::string()>, boost ::any > >
vector< smacc2_msgs ::msg::SmaccTransitionLogEntry >
SMRunMode
long
SharedPtr
SharedPtr
#hh_
SharedPtr
SharedPtr
#transitionHistoryService_
#currentState_
#status_msg_
#orthogonals_
-eventQueueMutex_
-m_mutex_
-stateMachineCurrentAction
-stateCallbackConnections
-globalData_
-transitionLogHistory_
-runMode_
-stateSeqCounter
#timer_
#stateMachinePub_
#transitionLogPub_
#stateMachineStatusPub_
smacc2::ISmaccStateMachine
+ ISmaccStateMachine()
+ ~ISmaccStateMachine()
+ reset()
+ stop()
+ eStop()
+ getOrthogonal()
+ getOrthogonals()
+ requiresComponent()
+ postEvent()
+ postEvent()
+ getGlobalSMData()
+ setGlobalSMData()
+ mapBehavior()
+ getStateMachineName()
+ state_machine_visualization()
+ getCurrentStateInfo()
+ publishTransition()
+ onInitialize()
+ getTransitionLogHistory()
+ createSignalConnection()
+ notifyOnStateEntryStart()
+ notifyOnStateEntryEnd()
+ notifyOnRuntimeConfigured()
+ notifyOnStateExiting()
+ notifyOnStateExited()
+ disposeStateAndDisconnect Signals()
+ notifyOnRuntimeConfiguration Finished()
+ getCurrentStateCounter()
+ getCurrentState()
+ getStateMachineInfo()
+ buildStateMachineInfo()
+ getNode()
+ getLogger()
+ getMutex()
# checkStateMachineConsistence()
# initializeROS()
# onInitialized()
# createOrthogonal()
- propagateEventToStateReactors()
- updateStatusMessage()
vector< std::shared _ptr< smacc2::ISmaccClient Behavior > >
vector< std::shared _ptr< smacc2::ISmaccClient > >
double
processor_handle
-statusPub_
thread
vector< smacc2::ISmaccUpdatable * >
atomic< unsigned long >
atomic< bool >
SmaccFifoScheduler *
-clientBehaviors_
#clients_
-stateMachine_
-topicName_
-loop_rate_hz
-signalDetector_
-smaccStateMachine_
-processorHandle_
-signalDetectorThread_
-updatableClients_
-updatableStateElements_
-lastState_
-end_
-initialized_
-scheduler_
smacc2::ISmaccOrthogonal
+ setStateMachine()
+ getStateMachine()
+ addClientBehavior()
+ runtimeConfigure()
+ onEntry()
+ onExit()
+ getName()
+ requiresComponent()
+ requiresClient()
+ getClients()
+ getClientBehaviors()
+ getGlobalSMData()
+ getGlobalSMData()
+ getClientBehavior()
+ getNode()
+ getLogger()
# onInitialize()
# initializeClients()
# assignClientToOrthogonal()
smacc2::SignalDetector
+ SignalDetector()
+ initialize()
+ setProcessorHandle()
+ runThread()
+ join()
+ stop()
+ pollingLoop()
+ pollOnce()
+ postEvent()
+ getNode()
+ getLogger()
- findUpdatableClientsAndComponents()
- findUpdatableStateElements()
-topicName_
map< smacc2::ComponentKey, std::shared_ptr< smacc2 ::ISmaccComponent > >
-stateMachine_
-topicName_
-orthogonal_
#components_
#stateMachine_
smacc2::ISmaccClient
+ ISmaccClient()
+ ~ISmaccClient()
+ onInitialize()
+ getName()
+ getComponent()
+ getComponent()
+ getComponent()
+ getType()
+ getStateMachine()
+ connectSignal()
+ requiresClient()
+ getComponents()
+ postEvent()
+ postEvent()
# onOrthogonalAllocation()
# createComponent()
# createNamedComponent()
# getNode()
# getLogger()
- initialize()
- setStateMachine()
- setOrthogonal()
#owner_
smacc2::ISmaccComponent
+ ISmaccComponent()
+ ~ISmaccComponent()
+ getName()
# onInitialize()
# postEvent()
# postEvent()
# onOrthogonalAllocation()
# requiresComponent()
# requiresClient()
# createSiblingComponent()
# createSiblingNamedComponent()
# getNode()
# getLogger()
# getStateMachine()
- initialize()
- setStateMachine()
+goalToleranceMeters_
bool
optional< rmw_qos_durability _policy_t >
SharedPtr
optional< rmw_qos_reliability _policy_t >
optional< int >
-initialized_
+durability
-pub_
+reliability
+queueSize
smacc2::components ::CpTopicPublisher< MessageType >
+ CpTopicPublisher()
+ ~CpTopicPublisher()
+ publish()
+ onInitialize()
SharedPtr
SharedPtr
-initialized_
+durability
-initialized_
+durability
+reliability
+reliability
+queueSize
+queueSize
-pub_
-pub_
< geometry_msgs::msg ::PoseWithCovarianceStamped >
< geometry_msgs::msg ::PoseStamped >
smacc2::components ::CpTopicPublisher< geometry_msgs::msg:: PoseWithCovarianceStamped >
+ CpTopicPublisher()
+ ~CpTopicPublisher()
+ publish()
+ onInitialize()
smacc2::components ::CpTopicPublisher< geometry_msgs::msg:: PoseStamped >
+ CpTopicPublisher()
+ ~CpTopicPublisher()
+ publish()
+ onInitialize()
optional< geometry _msgs::msg::PoseWithCovariance Stamped >
optional< geometry _msgs::msg::PoseStamped >
function< void(const geometry_msgs::msg:: PoseWithCovarianceStamped &)>
function< void()>
+cppubLocation_
+cpppubGoalPose_
+lastPose_
+lastGoal_
+postEvAutoLocalized_
+postEvGoalReached_
sm_autoware_avp::clients ::CIAutoware
+ onOrthogonalAllocation()
+ onInitialize()
+ checkGoalReached()
+ onNdtPoseReceived()
+ publishGoalPose()
+ publishInitialPoseEstimation()