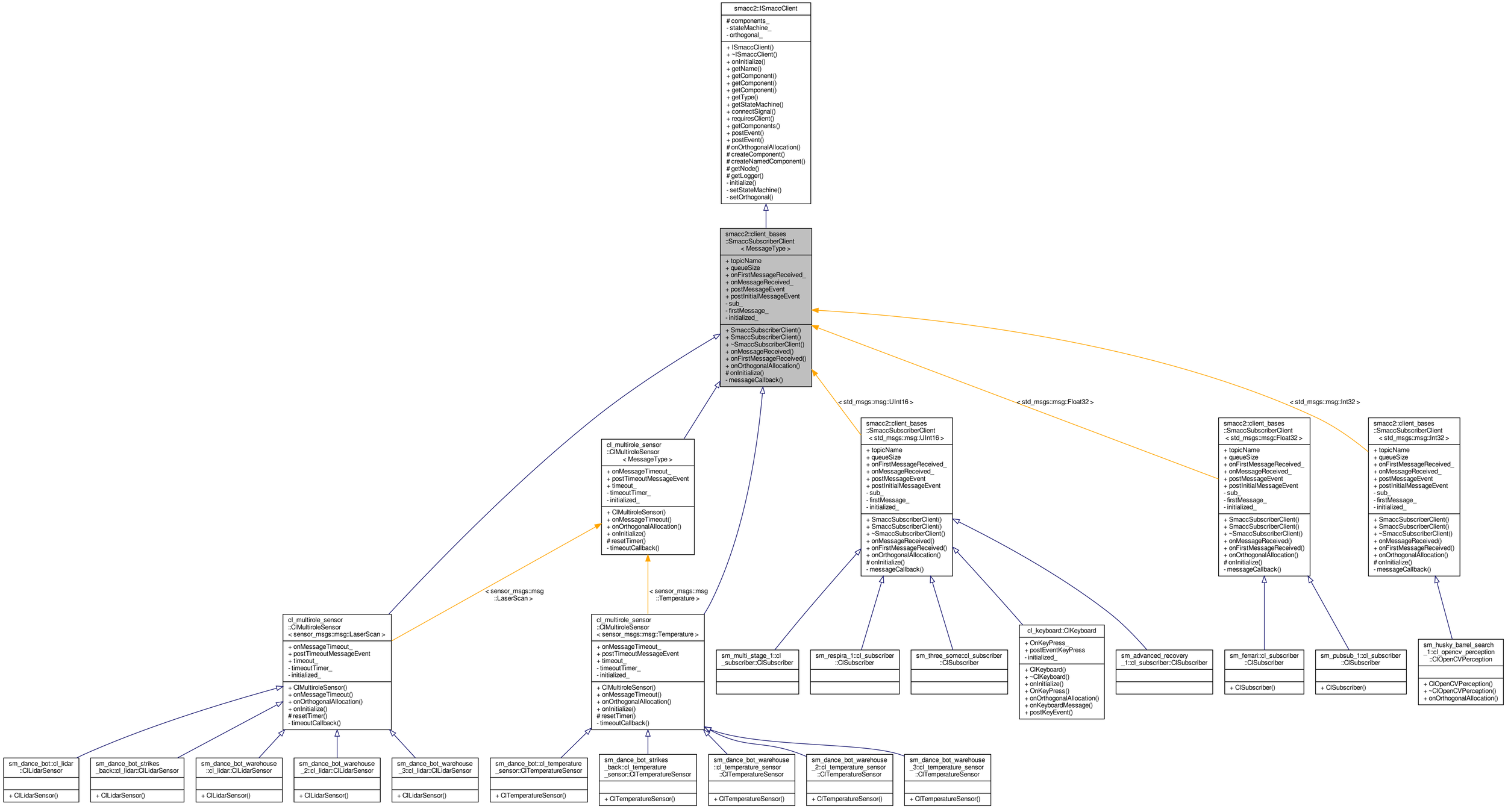
smacc2::ISmaccClient
components_
- stateMachine_
- orthogonal_
+ ISmaccClient()
+ ~ISmaccClient()
+ onInitialize()
+ getName()
+ getComponent()
+ getComponent()
+ getComponent()
+ getType()
+ getStateMachine()
+ connectSignal()
+ requiresClient()
+ getComponents()
+ postEvent()
+ postEvent()
# onOrthogonalAllocation()
# createComponent()
# createNamedComponent()
# getNode()
# getLogger()
- initialize()
- setStateMachine()
- setOrthogonal()
smacc2::client_bases ::SmaccSubscriberClient < MessageType >
+ topicName
+ queueSize
+ onFirstMessageReceived_
+ onMessageReceived_
+ postMessageEvent
+ postInitialMessageEvent
- sub_
- firstMessage_
- initialized_
+ SmaccSubscriberClient()
+ SmaccSubscriberClient()
+ ~SmaccSubscriberClient()
+ onMessageReceived()
+ onFirstMessageReceived()
+ onOrthogonalAllocation()
# onInitialize()
- messageCallback()
< std_msgs::msg::UInt16 >
< std_msgs::msg::Float32 >
< std_msgs::msg::Int32 >
cl_multirole_sensor ::ClMultiroleSensor < MessageType >
+ onMessageTimeout_
+ postTimeoutMessageEvent
+ timeout_
- timeoutTimer_
- initialized_
+ ClMultiroleSensor()
+ onMessageTimeout()
+ onOrthogonalAllocation()
+ onInitialize()
# resetTimer()
- timeoutCallback()
smacc2::client_bases ::SmaccSubscriberClient < std_msgs::msg::UInt16 >
+ topicName
+ queueSize
+ onFirstMessageReceived_
+ onMessageReceived_
+ postMessageEvent
+ postInitialMessageEvent
- sub_
- firstMessage_
- initialized_
+ SmaccSubscriberClient()
+ SmaccSubscriberClient()
+ ~SmaccSubscriberClient()
+ onMessageReceived()
+ onFirstMessageReceived()
+ onOrthogonalAllocation()
# onInitialize()
- messageCallback()
smacc2::client_bases ::SmaccSubscriberClient < std_msgs::msg::Float32 >
+ topicName
+ queueSize
+ onFirstMessageReceived_
+ onMessageReceived_
+ postMessageEvent
+ postInitialMessageEvent
- sub_
- firstMessage_
- initialized_
+ SmaccSubscriberClient()
+ SmaccSubscriberClient()
+ ~SmaccSubscriberClient()
+ onMessageReceived()
+ onFirstMessageReceived()
+ onOrthogonalAllocation()
# onInitialize()
- messageCallback()
smacc2::client_bases ::SmaccSubscriberClient < std_msgs::msg::Int32 >
+ topicName
+ queueSize
+ onFirstMessageReceived_
+ onMessageReceived_
+ postMessageEvent
+ postInitialMessageEvent
- sub_
- firstMessage_
- initialized_
+ SmaccSubscriberClient()
+ SmaccSubscriberClient()
+ ~SmaccSubscriberClient()
+ onMessageReceived()
+ onFirstMessageReceived()
+ onOrthogonalAllocation()
# onInitialize()
- messageCallback()
< sensor_msgs::msg ::LaserScan >
< sensor_msgs::msg ::Temperature >
cl_multirole_sensor ::ClMultiroleSensor < sensor_msgs::msg::LaserScan >
+ onMessageTimeout_
+ postTimeoutMessageEvent
+ timeout_
- timeoutTimer_
- initialized_
+ ClMultiroleSensor()
+ onMessageTimeout()
+ onOrthogonalAllocation()
+ onInitialize()
# resetTimer()
- timeoutCallback()
cl_multirole_sensor ::ClMultiroleSensor < sensor_msgs::msg::Temperature >
+ onMessageTimeout_
+ postTimeoutMessageEvent
+ timeout_
- timeoutTimer_
- initialized_
+ ClMultiroleSensor()
+ onMessageTimeout()
+ onOrthogonalAllocation()
+ onInitialize()
# resetTimer()
- timeoutCallback()
sm_multi_stage_1::cl _subscriber::ClSubscriber
sm_respira_1::cl_subscriber ::ClSubscriber
sm_three_some::cl_subscriber ::ClSubscriber
cl_keyboard::ClKeyboard
+ OnKeyPress_
+ postEventKeyPress
- initialized_
+ ClKeyboard()
+ ~ClKeyboard()
+ onInitialize()
+ OnKeyPress()
+ onOrthogonalAllocation()
+ onKeyboardMessage()
+ postKeyEvent()
sm_advanced_recovery _1::cl_subscriber::ClSubscriber
sm_ferrari::cl_subscriber ::ClSubscriber
+ ClSubscriber()
sm_pubsub_1::cl_subscriber ::ClSubscriber
+ ClSubscriber()
sm_husky_barrel_search _1::cl_opencv_perception ::ClOpenCVPerception
+ ClOpenCVPerception()
+ ~ClOpenCVPerception()
+ onOrthogonalAllocation()
sm_dance_bot::cl_lidar ::ClLidarSensor
+ ClLidarSensor()
sm_dance_bot_strikes _back::cl_lidar::ClLidarSensor
+ ClLidarSensor()
sm_dance_bot_warehouse ::cl_lidar::ClLidarSensor
+ ClLidarSensor()
sm_dance_bot_warehouse _2::cl_lidar::ClLidarSensor
+ ClLidarSensor()
sm_dance_bot_warehouse _3::cl_lidar::ClLidarSensor
+ ClLidarSensor()
sm_dance_bot::cl_temperature _sensor::ClTemperatureSensor
+ ClTemperatureSensor()
sm_dance_bot_strikes _back::cl_temperature _sensor::ClTemperatureSensor
+ ClTemperatureSensor()
sm_dance_bot_warehouse ::cl_temperature_sensor ::ClTemperatureSensor
+ ClTemperatureSensor()
sm_dance_bot_warehouse _2::cl_temperature_sensor ::ClTemperatureSensor
+ ClTemperatureSensor()
sm_dance_bot_warehouse _3::cl_temperature_sensor ::ClTemperatureSensor
+ ClTemperatureSensor()