string
shared_ptr< smacc2 ::introspection::SmaccState MachineInfo >
shared_ptr< smacc2 ::introspection::SmaccState Info >
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 ::ClientBehaviorInfoEntry > >
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 > > >
+demangledStateName +fullStateName
+stateMachine_
+parentState_
+depth_ +stateIndex_
+transitions_
+children_
+tid_
+staticBehaviorInfo
+stateReactorsInfo
+eventGeneratorsInfo
smacc2::introspection ::SmaccStateInfo
+ SmaccStateInfo()
+ getStateLevel()
+ depth()
+ getAncestors()
+ getFullPath()
+ createChildState()
+ declareTransition()
+ toShortName()
+ getDemangledFullName()
+ getNode()
+ getLogger()
SharedPtr
shared_ptr< rclcpp ::Logger >
vector< std::shared _ptr< smacc2::StateReactor > >
vector< std::shared _ptr< smacc2::SmaccEventGenerator > >
#stateMachineInfo_
+node_
+logger_
#stateReactors_
#eventGenerators_
#currentStateInfo_
#stateInfo_
#nh_
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
SharedPtr
SharedPtr
SharedPtr
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
#stateMachineStatusPub_
#timer_
#stateMachinePub_
#transitionLogPub_
#transitionHistoryService_
#status_msg_
#orthogonals_
-eventQueueMutex_ -m_mutex_
-stateMachineCurrentAction
-stateCallbackConnections
-globalData_
-transitionLogHistory_
-runMode_
-stateSeqCounter_
#currentState_
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()
+ notifyOnStateExitting()
+ notifyOnStateExited()
+ disposeStateAndDisconnect Signals()
+ notifyOnRuntimeConfiguration Finished()
+ getCurrentStateCounter()
+ getCurrentState()
+ getStateMachineInfo()
+ buildStateMachineInfo()
+ getNode()
+ getLogger()
+ getMutex()
# checkStateMachineConsistence()
# initializeROS()
# onInitialized()
# createOrthogonal()
- propagateEventToStateReactors()
- updateStatusMessage()
-currentState
#name_
atomic< unsigned long >
atomic< bool >
SmaccFifoScheduler *
processor_handle
thread
vector< smacc2::ISmaccUpdatable * >
-statusPub_
double
vector< std::shared _ptr< smacc2::ISmaccClient Behavior > >
vector< std::shared _ptr< smacc2::ISmaccClient > >
+action_endpoint_
+action_endpoint_
-lastState_
-end_ -initialized_
-scheduler_
-processorHandle_
-signalDetectorThread_
-updatableClients_ -updatableStateElements_
#currentPathName_ #odomFrame_ #odomTopicName_
-loop_rate_hz
-smaccStateMachine_
-clientBehaviors_
-signalDetector_
#clients_
-stateMachine_
smacc2::SignalDetector
+ SignalDetector()
+ initialize()
+ setProcessorHandle()
+ runThread()
+ join()
+ stop()
+ pollingLoop()
+ pollOnce()
+ postEvent()
+ getNode()
+ getLogger()
- findUpdatableClientsAndComponents()
- findUpdatableStateElements()
map< smacc2::ComponentKey, std::shared_ptr< smacc2 ::ISmaccComponent > >
boost::signals2::signal < Signature, optional _last_value< typename boost ::function_traits< Signature >::result_type >, int, std ::less< int >, function< Signature >, typename extended_signature< function_traits< Signature >::arity, Signature >::function_type, boost:: signals2::mutex >
smacc2::ISmaccOrthogonal
+ setStateMachine()
+ getStateMachine()
+ addClientBehavior()
+ runtimeConfigure()
+ onEntry()
+ onExit()
+ getName()
+ requiresComponent()
+ requiresClient()
+ getClients()
+ getClientBehaviors()
+ setGlobalSMData()
+ getGlobalSMData()
+ getClientBehavior()
+ getNode()
+ getLogger()
# onInitialize()
# initializeClients()
# assignClientToOrthogonal()
-stateMachine_
-stateMachine_
#stateMachine_
#components_
-orthogonal_
-currentOrthogonal
smacc2::ISmaccClient
+ ISmaccClient()
+ ~ISmaccClient()
+ onInitialize()
+ getName()
+ getComponent()
+ getComponent()
+ getComponent()
+ getType()
+ getStateMachine()
+ connectSignal()
+ requiresClient()
+ getComponents()
+ postEvent()
+ postEvent()
# onOrthogonalAllocation()
# createComponent()
# createNamedComponent()
# getNode()
# getLogger()
- initialize()
- setStateMachine()
- setOrthogonal()
smacc2::ISmaccClientBehavior
+ ISmaccClientBehavior()
+ ~ISmaccClientBehavior()
+ getStateMachine()
+ getName()
+ requiresClient()
+ requiresComponent()
# runtimeConfigure()
# onEntry()
# onExit()
# postEvent()
# postEvent()
# getCurrentState()
# dispose()
# getNode()
# getLogger()
- executeOnEntry()
- executeOnExit()
- onOrthogonalAllocation()
#clearAngularDistanceThreshold _
#clearPointDistanceThreshold _
#recordAngularDistanceThreshold _
#recordPointDistanceThreshold_
boost::signals2::signal < void(const WrappedResult &), optional_last_value < typename boost::function _traits< void(const WrappedResult &) >::result_type >, int, std ::less< int >, function< void(const WrappedResult &) >, typename extended _signature< function_traits< void(const WrappedResult &) >::arity, void(const WrappedResult &) >::function_type, boost::signals2::mutex >
smacc2::SmaccSignal < Signature, Combiner, Group, GroupCompare, SlotFunction, ExtendedSlotFunction, Mutex >
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 >
< void(const WrappedResult &)>
< void()>
#owner_
smacc2::ISmaccComponent
+ ISmaccComponent()
+ ~ISmaccComponent()
+ getName()
# onInitialize()
# postEvent()
# postEvent()
# onOrthogonalAllocation()
# requiresComponent()
# requiresClient()
# createSiblingComponent()
# createSiblingNamedComponent()
# getNode()
# getLogger()
# getStateMachine()
- initialize()
- setStateMachine()
SharedPtr
smacc2::SmaccSignal < void(const WrappedResult &)>
FeedbackCallback
function< void(WrappedResult)>
SharedPtr
function< void(const Feedback &)>
ResultCallback
optional< std::shared _future< typename GoalHandle ::SharedPtr > >
smacc2::SmaccSignal < void()>
smacc2::client_bases ::ISmaccActionClient
+ ISmaccActionClient()
+ ~ISmaccActionClient()
+ getNamespace()
+ cancelGoal()
+ getClientBase()
+ getName()
future< int >
function< void()>
bool
SharedPtr
SharedPtr
Path
WorkingMode
vector< nav_msgs::msg ::Path >
vector< cl_nav2z::odom _tracker::OdomTracker ::PathInfo >
mutex
optional< geometry _msgs::msg::PoseStamped >
+goalHandle_
+onAborted_ +onCancelled_ +onSucceeded_
+feedback_cb
+postAbortedEvent +postCancelledEvent +postSuccessEvent
#client_
+postFeedbackEvent
+done_cb
+lastRequest_
-onFailure_ -onFinished_ -onSuccess_
-onEntryThread_ -onExitThread_
-postFailureEventFn _ -postFinishEventFn _ -postSuccessEventFn_
-isShutdownRequested_
#publishMessages #subscribeToOdometryTopic_
#robotBasePathPub_ #robotBasePathStackedPub_
#odomSub_
#aggregatedStackPathMsg _ #baseTrajectory_
#workingMode_
#pathStack_
#pathInfos_
#m_mutex_
#currentMotionGoal_
smacc2::client_bases ::SmaccActionClientBase < ActionType >
+ SmaccActionClientBase()
+ SmaccActionClientBase()
+ ~SmaccActionClientBase()
+ getClientBase()
+ onInitialize()
+ postResultEvent()
+ onOrthogonalAllocation()
+ onSucceeded()
+ onSucceeded()
+ onAborted()
+ onAborted()
+ onCancelled()
+ onCancelled()
+ cancelGoal()
+ sendGoal()
+ getEventLabel()
# onFeedback()
# onResult()
smacc2::SmaccAsyncClient Behavior
+ onOrthogonalAllocation()
+ ~SmaccAsyncClientBehavior()
+ onSuccess()
+ onFinished()
+ onFailure()
# postSuccessEvent()
# postFailureEvent()
# dispose()
# isShutdownRequested()
- waitFutureIfNotFinished()
- executeOnEntry()
- executeOnExit()
cl_nav2z::odom_tracker ::OdomTracker
+ OdomTracker()
+ processOdometryMessage()
+ setWorkingMode()
+ setPublishMessages()
+ pushPath()
+ pushPath()
+ popPath()
+ clearPath()
+ setStartPoint()
+ setStartPoint()
+ setCurrentMotionGoal()
+ setCurrentPathName()
+ getCurrentMotionGoal()
+ getPath()
+ logStateString()
# onInitialize()
# updateConfiguration()
# rtPublishPaths()
# updateRecordPath()
# updateClearPath()
# updateAggregatedStackPath()
< nav2_msgs::action ::NavigateToPose >
+goalHandle_
+onAborted_ +onCancelled_ +onSucceeded_
+feedback_cb
+postAbortedEvent +postCancelledEvent +postSuccessEvent
#client_
+postFeedbackEvent
+done_cb
+lastRequest_
smacc2::client_bases ::SmaccActionClientBase < nav2_msgs::action::NavigateTo Pose >
+ SmaccActionClientBase()
+ SmaccActionClientBase()
+ ~SmaccActionClientBase()
+ getClientBase()
+ onInitialize()
+ postResultEvent()
+ onOrthogonalAllocation()
+ onSucceeded()
+ onSucceeded()
+ onAborted()
+ onAborted()
+ onCancelled()
+ onCancelled()
+ cancelGoal()
+ sendGoal()
+ getEventLabel()
# onFeedback()
# onResult()
#goalPose_
#odomTracker_
cl_nav2z::ClNav2Z
+ ClNav2Z()
+ ~ClNav2Z()
ResultCode
#moveBaseClient_
#navigationResult_
cl_nav2z::CbNav2ZClientBehaviorBase
+ ~CbNav2ZClientBehaviorBase()
+ onOrthogonalAllocation()
- propagateSuccessEvent()
- propagateFailureEvent()
optional< float >
optional< geometry _msgs::msg::Quaternion >
optional< std::string >
#forwardDistance_ +forwardSpeed
+forceInitialOrientation
+goalChecker_
cl_nav2z::CbNavigateForward
+ CbNavigateForward()
+ CbNavigateForward()
+ CbNavigateForward()
+ ~CbNavigateForward()
+ onEntry()
+ onExit()
+ setForwardDistance()