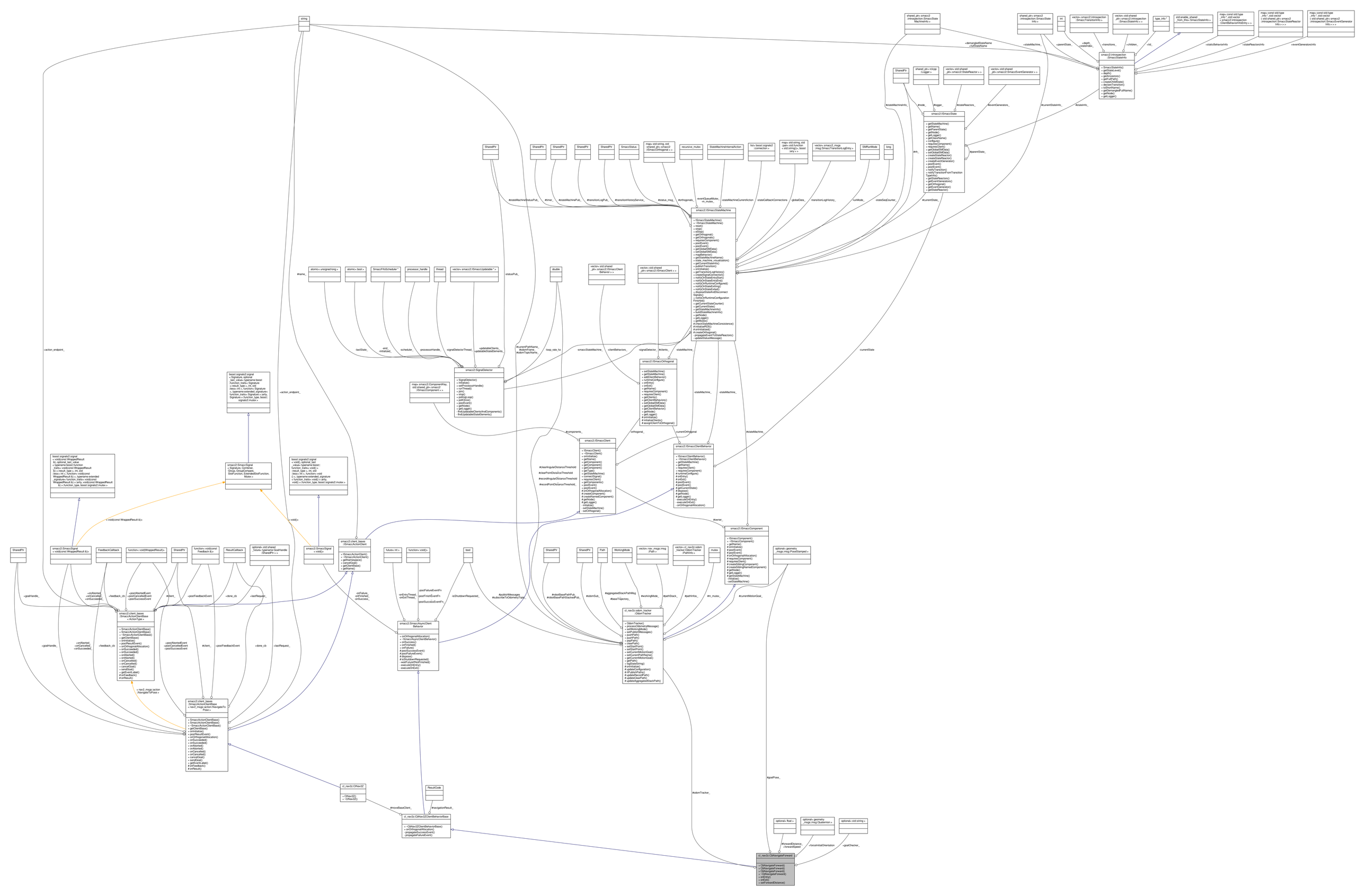
string
shared_ptr< smacc2 ::introspection::SmaccStateMachineInfo >
shared_ptr< smacc2 ::introspection::SmaccState Info >
int
vector< smacc2::introspection ::SmaccTransitionInfo >
vector< std::shared _ptr< smacc2::introspection ::SmaccStateInfo > >
Type_info *
std::enable_shared from_this< SmaccStateInfo >
map< const std::type _info *, std::vector < smacc2::introspection ::SmaccStateReactor Info > > >
map< const std::type _info *, std::vector < std::shared_ptr< smacc2 ::introspection::SmaccEventGenerator Info > > >
map< const std::type _info *, std::vector < std::shared_ptr< smacc2::introspection::SmaccEventGenerator Info > > >
+demangledStateName
+fullStateName
+stateMachine_
+parentState_
+depth
+stateIndex_
+transitions_
+children_
+id_
+staticBehaviorInfo
+stateReactorsInfo
+eventGeneratorsInfo
smacc2::introspection ::SmaccStateInfo
+ SmaccStateInfo()
+ getFullName()
+ depth()
+ getAncestors()
+ getFullPath()
+ createChildState()
+ getStateMachine()
+ 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
#fn_
#parentState_
smacc2::ISmaccState
+ getStateMachine()
+ getName()
+ getStateName()
+ getNode()
+ getLogger()
+ getStateNameIn()
+ getPath()
+ notifyExitAll()
+ requiresComponent()
+ requiresClient()
+ getGlobalSMData()
+ setGlobalSMData()
+ createStateReactor()
+ createStateReactor()
+ createEventGenerator()
+ postEvent()
+ postEvent()
+ notifyTransition()
+ notifyTransitionFromTransition TypeInfo()
+ getStateReactors()
+ getEventGenerators()
+ getOrthogonal()
+ getEventGenerator()
+ getStateReactor()
#currentState_
smacc2::ISmaccStateMachine
+ ISmaccStateMachine()
+ ~ISmaccStateMachine()
+ start()
+ stop()
+ eStop()
+ getOrthogonal()
+ getOrthogonals()
+ getOrthogonalComponent()
+ postEvent()
+ postEvent()
+ getGlobalSMData()
+ setGlobalSMData()
+ mapBehavior()
+ getStateMachineName()
+ state_machine_visualization()
+ publishTransition()
+ publishTransition()
+ onInitialize()
+ getTransitionLogHistory()
+ createSignalConnection()
+ notifyOnStateEntryStart()
+ notifyOnStateEntryEnd()
+ notifyOnRuntimeConfigured()
+ notifyOnStateExiting()
+ notifyOnStateExited()
+ notifyOnStateAndXDisconnect Signals()
+ notifyOnRuntimeConfiguration Started()
+ getCurrentStateCounter()
+ getCurrentState()
+ getStateMachineInfo()
+ buildStateMachineInfo()
+ getNode()
+ getLogger()
+ getMutex()
# checkStateMachineConsistency()
# initialiseROS()
# createClients()
# createOrthogonal()
- propagateEventToStateReactors()
- updateStatusMessage()
#currentOrthogonal_
#orthogonals_
#transitionLogHistory_
#runMode_
#stateSeqCounter_
#mutex_
#eventQueueMutex_
#m_mutex_
#stateMachineCurrentAction
#stateCallbackConnections
#globalData_
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 ::smacc_transition_log_entry >
SMRunMode
long
#statusPub_
#name_
atomic< unsigned long >
atomic< bool >
SmaccFifoScheduler *
processor_handle
thread
vector< smacc2::ISmaccUpdatable * >
double
vector< std::shared _ptr< smacc2::ISmaccClient Behavior > >
vector< std::shared _ptr< smacc2::ISmaccClient > >
#currentPathName_
#odomFrame_
#odomTopicName_
#loop_rate_hz
#smaccStateMachine_
#clientBehaviors_
#signalDetector_
#clients_
#stateMachine_
#currentState
-end_
-initialized_
-lastState_
-scheduler_
-processorHandle_
-signalDetectorThread_
-updatableClients_
-updatableStateElements_
smacc2::SignalDetector
+ SignalDetector()
+ initialize()
+ setProcessorHandle()
+ runThread()
+ join()
+ stop()
+ pollOnce()
+ getOrAcc()
+ postEvent()
+ getWorld()
+ getLogger()
+ findUpdatableClientsAndComponents()
- findUpdatableStateElements()
map< smacc2::ComponentKey, std::shared_ptr< smacc2 ::ISmaccComponent > >
smacc2::ISmaccOrthogonal
+ getStateMachine()
+ getStateMachine()
+ addClientBehavior()
+ runtimeConfigure()
+ onEntry()
+ onExit()
+ getName()
+ requiresComponent()
+ requiresClient()
+ getClient()
+ getClientBehavior()
+ setGlobalSMData()
+ getGlobalSMData()
+ getClientBehavior()
+ getLogger()
# getLogger()
# onInitialize()
# initializeClients()
# assignClientToOrthogonal()
#orthogonal_
#currentOrthogonal
#stateMachine_
#stateMachine_
#stateMachine_
#components_
smacc2::ISmaccClient
+ ISmaccClient()
+ ~ISmaccClient()
+ onInitialize()
+ getName()
+ getComponent()
+ getComponent()
+ getComponent()
+ getTypeId()
+ getStateMachine()
+ connectSignal()
+ getComponents()
+ getComponents()
+ postEvent()
+ postEvent()
# onOrthogonalAllocation()
# createComponent()
# createNamedComponent()
# getNodeId()
# getLogger()
- initialize()
- setStateMachine()
- setOrthogonal()
#clearAngularDistanceThreshold
#clearPointDistanceThreshold
#recordAngularDistanceThreshold
#recordPointDistanceThreshold_
smacc2::ISmaccClientBehavior
+ ~ISmaccClientBehavior()
+ getStateMachine()
+ onEntry()
+ requiresClient()
+ requiresComponent()
+ runtimeConfigure()
+ onEntry()
+ onExit()
+ postEvent()
+ postEvent()
+ getOrthogonal()
# $dispose()
# getNodeId()
# getLogger()
- executeOnEntry()
- executeOnExit()
- onOrthogonalAllocation()
#owner_
smacc2::ISmaccComponent
+ ISmaccComponent()
+ ~ISmaccComponent()
+ getName()
+ getStateMachine()
# postEvent()
# postEvent()
# onOrthogonalAllocation()
# requiresComponent()
# requiresClient()
# createSiblingComponent()
# createSiblingNamedComponent()
# getNodeId()
# getLogger()
- initialize()
- initialize()
- setStateMachine()
boost::signals2::signal
+ signature, optional
_last_value< typename boost ::function_traits< Signature ::result_type >, function_ traits< Signature ::result_type >, typename extended_signature< function_traits< Signature >::arity, Signature > ::function_type, boost ::signals2::mutex >
boost::signals2::signal
< void(const WrappedResult &), boost::signals2::detail ::optional_last_value< WrappedResult &>::result_type, int, std ::less< int >, function< void(const WrappedResult &) >, typename extended_signature< function_traits< Signature >::arity, Signature >::function_type, boost::signals2::mutex >
boost::signals2::signal
< void(), optional_last_value< WrappedResult>, int, std ::less< int >, function< void() >, typename extended_signature< function_traits< void() >::arity, void() >::function_type, boost::signals2::mutex >
smacc2::SmaccSignal
< Signature, Combiner, Group, GroupCompare, SlotFunction, ExtendedSlotFunction, Mutex >
smacc2::SmaccSignal
< void(const WrappedResult &)>
smacc2::SmaccSignal
< void()>
< void(const WrappedResult &)>
void()>
smacc2::client_bases ::ISmaccActionClient
+ ISmaccActionClient()
+ ~ISmaccActionClient()
+ getNamespace()
+ cancelGoal()
+ getClientState()
+ getName()
#actionClient_
#timer_
#stateMachinePub_
#transitionLogPub_
#transitionHistoryService_
#status_msg_
SharedPtr
SharedPtr
FeedbackCallback
function< void(WrappedResult)>
SharedPtr
function< void(const Feedback &)>
ResultCallback
optional< std::shared _future< typename GoalHandle ::SharedPtr > >
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_
smacc2::client_bases ::SmaccActionClientBase < ActionType >
+ SmaccActionClientBase()
+ SmaccActionClientBase()
+ ~SmaccActionClientBase()
+ getClientBase()
+ onInitialize()
+ onOrthogonalEvent()
+ onOrthogonalAllocation()
+ onSucceeded()
+ onSucceeded()
+ onAborted()
+ onAborted()
+ onCancelled()
+ onCancelled()
+ cancelGoal()
+ sendGoal()
+ getEventLabel()
# onFeedback()
# onResult()
< nav2_msgs::action ::NavigateToPose >
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()
smacc2::SmaccAsyncClient Behavior
+ onOrthogonalAllocation()
+ ~SmaccAsyncClientBehavior()
+ onSuccess()
+ onFinished()
+ onFailure()
# postSuccessEvent()
# postFailureEvent()
# dispose()
# isShutdownRequested()
- waitFutureIsNotFinished()
- onEntryOnExit()
- executeOnExit()
#isShutdownRequested_
#postFailureEventFn
#postFinishEventFn
#postSuccessEventFn
#onEntryThread_
#onExitThread_
#publishMessages
#subscribeToOdometryTopic
SharedPtr
SharedPtr
Path
WorkingMode
vector< nav_msgs::msg ::Path >
vector< cl_nav2z::odom _tracker::OdomTracker ::PathInfo >
mutex
#robotBasePathPub_
#robotBasePathStackedPub_
#odomSub_
#aggregatedStackPathMsg
#baseTrajectory_
#workingMode_
#pathStack_
#pathInfos_
#m_mutex_
cl_nav2z::odom_tracker ::OdomTracker
+ OdomTracker()
+ processOdometryMessage()
+ setWorkingMode()
+ setPubVisMessages()
+ pushPath()
+ pushPath()
+ popPath()
+ clearPath()
+ setStartPoint()
+ setStartPoint()
+ setCurrentMotionGoal()
+ setCurrentPathName()
+ setCurrentMotionGoal()
+ getPath()
+ logStateStrings()
# onInitialize()
# updateConfiguration()
# updatePath()
# updateRecordPath()
# updateClearPath()
# updateAggregatedStackPath()
#currentMotionGoal_
#odomTracker_
#goalPose_
cl_nav2z::CINav2Z
+ CINav2Z()
+ ~CINav2Z()
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()