cl_nav2z::CbNavigateForward
+ CbNavigateForward()
+ CbNavigateForward()
+ CbNavigateForward()
+ ~CbNavigateForward()
+ onEntry()
+ onExit()
+ setForwardDistance()
optional< float >
#forwardDistance_
+forwardSpeed
optional< geometry_msgs::msg::Quaternion >
+forceInitialOrientation
optional< std::string >
+goalChecker_
optional< geometry_msgs::msg::PoseStamped >
#goalPose_
#currentMotionGoal_
#odomTracker_
cl_nav2z::CbNav2ZClientBehaviorBase
+ ~CbNav2ZClientBehaviorBase()
+ onOrthogonalAllocation()
- propagateSuccessEvent()
- propagateFailureEvent()
ResultCode
#navigationResult_
#moveBaseClient_
cl_nav2z::ClNav2Z
+ ClNav2Z()
+ ~ClNav2Z()
smacc2::SmaccAsyncClientBehavior
+ onOrthogonalAllocation()
+ ~SmaccAsyncClientBehavior()
+ onSuccess()
+ onFinished()
+ onFailure()
# postSuccessEvent()
# postFailureEvent()
# dispose()
# isShutdownRequested()
- waitFutureIfNotFinished()
- executeOnEntry()
- executeOnExit()
future< int >
-onEntryThread_
-onExitThread_
function< void()>
-postFailureEventFn_
-postFinishEventFn_
-postSuccessEventFn_
bool
-isShutdownRequested_
#publishMessages
#subscribeToOdometryTopic_
-onFailure_
-onFinished_
-onSuccess_
smacc2::client_bases::SmaccActionClientBase< nav2_msgs::action::NavigateToPose >
+ SmaccActionClientBase()
+ SmaccActionClientBase()
+ ~SmaccActionClientBase()
+ getClientBase()
+ onInitialize()
+ postResultEvent()
+ onOrthogonalAllocation()
+ onSucceeded()
+ onSucceeded()
+ onAborted()
+ onAborted()
+ onCancelled()
+ onCancelled()
+ cancelGoal()
+ sendGoal()
+ getEventLabel()
# onFeedback()
# onResult()
< nav2_msgs::action::NavigateToPose >
smacc2::client_bases::SmaccActionClientBase< ActionType >
+ SmaccActionClientBase()
+ SmaccActionClientBase()
+ ~SmaccActionClientBase()
+ getClientBase()
+ onInitialize()
+ postResultEvent()
+ onOrthogonalAllocation()
+ onSucceeded()
+ onSucceeded()
+ onAborted()
+ onAborted()
+ onCancelled()
+ onCancelled()
+ cancelGoal()
+ sendGoal()
+ getEventLabel()
# onFeedback()
# onResult()
SharedPtr
+goalHandle_
smacc2::SmaccSignal< void(const WrappedResult &)>
+onAborted_
+onCancelled_
+onSucceeded_
FeedbackCallback
+feedback_cb
function< void(WrappedResult)>
+postAbortedEvent
+postCancelledEvent
+postSuccessEvent
SharedPtr
#client_
function< void(const Feedback &)>
+postFeedbackEvent
ResultCallback
+done_cb
optional< std::shared_future< typename GoalHandle ::SharedPtr > >
+lastRequest_
+action_endpoint_
smacc2::SmaccSignal< void()>
< void(const WrappedResult &)>
< void()>
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< 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 >
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 >
smacc2::client_bases::ISmaccActionClient
+ ISmaccActionClient()
+ ~ISmaccActionClient()
+ getNamespace()
+ cancelGoal()
+ getClientBase()
+ getName()
string
#name_
#currentPathName_
#odomFrame_
#odomTopicName_
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()
SharedPtr
#robotBasePathPub_
#robotBasePathStackedPub_
SharedPtr
#odomSub_
Path
#aggregatedStackPathMsg_
#baseTrajectory_
WorkingMode
#workingMode_
vector< nav_msgs::msg::Path >
#pathStack_
vector< cl_nav2z::odom_tracker::OdomTracker::PathInfo >
#pathInfos_
mutex
#m_mutex_
double
-loop_rate_hz
#clearAngularDistanceThreshold_
#clearPointDistanceThreshold_
#recordAngularDistanceThreshold_
#recordPointDistanceThreshold_
smacc2::ISmaccComponent
+ ISmaccComponent()
+ ~ISmaccComponent()
+ getName()
# onInitialize()
# postEvent()
# postEvent()
# onOrthogonalAllocation()
# requiresComponent()
# requiresClient()
# createSiblingComponent()
# createSiblingNamedComponent()
# getNode()
# getLogger()
# getStateMachine()
- initialize()
- setStateMachine()
#owner_
#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()
map< smacc2::ComponentKey, std::shared_ptr< smacc2::ISmaccComponent > >
#components_
-orthogonal_
smacc2::ISmaccClientBehavior
+ ISmaccClientBehavior()
+ ~ISmaccClientBehavior()
+ getStateMachine()
+ getName()
+ requiresClient()
+ requiresComponent()
# runtimeConfigure()
# onEntry()
# onExit()
# postEvent()
# postEvent()
# getCurrentState()
# dispose()
# getNode()
# getLogger()
- executeOnEntry()
- executeOnExit()
- onOrthogonalAllocation()
-currentOrthogonal
-stateMachine_
+currentState
smacc2::ISmaccOrthogonal
+ setStateMachine()
+ getStateMachine()
+ addClientBehavior()
+ runtimeConfigure()
+ onEntry()
+ onExit()
+ getName()
+ requiresComponent()
+ requiresClient()
+ getClients()
+ getClientBehaviors()
+ setGlobalSMData()
+ getGlobalSMData()
+ getClientBehavior()
+ getNode()
+ getLogger()
# onInitialize()
# initializeClients()
# assignClientToOrthogonal()
vector< std::shared_ptr< smacc2::ISmaccClientBehavior > >
-clientBehaviors_
vector< std::shared_ptr< smacc2::ISmaccClient > >
#clients_
-stateMachine_
-signalDetector_
-smaccStateMachine_
smacc2::SignalDetector
+ SignalDetector()
+ initialize()
+ setProcessorHandle()
+ runThread()
+ join()
+ stop()
+ pollingLoop()
+ pollOnce()
+ postEvent()
+ getNode()
+ getLogger()
- findUpdatableClientsAndComponents()
- findUpdatableStateElements()
atomic< unsigned long >
-lastState_
atomic< bool >
-end_
-initialized_
SmaccFifoScheduler *
-scheduler_
processor_handle
-processorHandle_
thread
-signalDetectorThread_
vector< smacc2::ISmaccUpdatable * >
-updatableClients_
-updatableStateElements_
SharedPtr
-statusPub_
#stateMachineStatusPub_
SharedPtr
#timer_
SharedPtr
#stateMachinePub_
SharedPtr
#transitionLogPub_
SharedPtr
#transitionHistoryService_
SmaccStatus
#status_msg_
map< std::string, std::shared_ptr< smacc2::ISmaccOrthogonal > >
#orthogonals_
recursive_mutex
-eventQueueMutex_
-m_mutex_
StateMachineInternalAction
-stateMachineCurrentAction
list< boost::signals2::connection >
-stateCallbackConnections
map< std::string, std::pair< std::function< std::string()>, boost::any > >
-globalData_
vector< smacc2_msgs::msg::SmaccTransitionLogEntry >
-transitionLogHistory_
SMRunMode
-runMode_
long
-stateSeqCounter_
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()
+ disposeStateAndDisconnectSignals()
+ notifyOnRuntimeConfigurationFinished()
+ getCurrentStateCounter()
+ getCurrentState()
+ getStateMachineInfo()
+ buildStateMachineInfo()
+ getNode()
+ getLogger()
+ getMutex()
# checkStateMachineConsistence()
# initializeROS()
# onInitialized()
# createOrthogonal()
- propagateEventToStateReactors()
- updateStatusMessage()
#nh_
#stateMachineInfo_
#currentStateInfo_
#currentState_
smacc2::ISmaccState
+ getStateMachine()
+ getName()
+ getParentState()
+ getNode()
+ getLogger()
+ getClassName()
+ configure()
+ requiresComponent()
+ requiresClient()
+ getGlobalSMData()
+ setGlobalSMData()
+ createStateReactor()
+ createStateReactor()
+ createEventGenerator()
+ postEvent()
+ postEvent()
+ notifyTransition()
+ notifyTransitionFromTransitionTypeInfo()
+ getStateReactors()
+ getEventGenerators()
+ getOrthogonal()
+ getEventGenerator()
+ getStateReactor()
#parentState_
SharedPtr
#node_
shared_ptr< rclcpp::Logger >
#logger_
vector< std::shared_ptr< smacc2::StateReactor > >
#stateReactors_
vector< std::shared_ptr< smacc2::SmaccEventGenerator > >
#eventGenerators_
#stateInfo_
smacc2::introspection::SmaccStateInfo
+ SmaccStateInfo()
+ getStateLevel()
+ depth()
+ getAncestors()
+ getFullPath()
+ createChildState()
+ declareTransition()
+ toShortName()
+ getDemangledFullName()
+ getNode()
+ getLogger()
+demangledStateName
+fullStateName
shared_ptr< smacc2::introspection::SmaccStateMachineInfo >
+stateMachine_
shared_ptr< smacc2::introspection::SmaccStateInfo >
+parentState_
int
+depth_
+stateIndex_
vector< smacc2::introspection::SmaccTransitionInfo >
+transitions_
vector< std::shared_ptr< smacc2::introspection::SmaccStateInfo > >
+children_
type_info *
+tid_
std::enable_shared_from_this< SmaccStateInfo >
map< const std::type_info *, std::vector< smacc2::introspection::ClientBehaviorInfoEntry > >
+staticBehaviorInfo
map< const std::type_info *, std::vector< std::shared_ptr< smacc2::introspection::SmaccStateReactorInfo > > >
+stateReactorsInfo
map< const std::type_info *, std::vector< std::shared_ptr< smacc2::introspection::SmaccEventGeneratorInfo > > >
+eventGeneratorsInfo