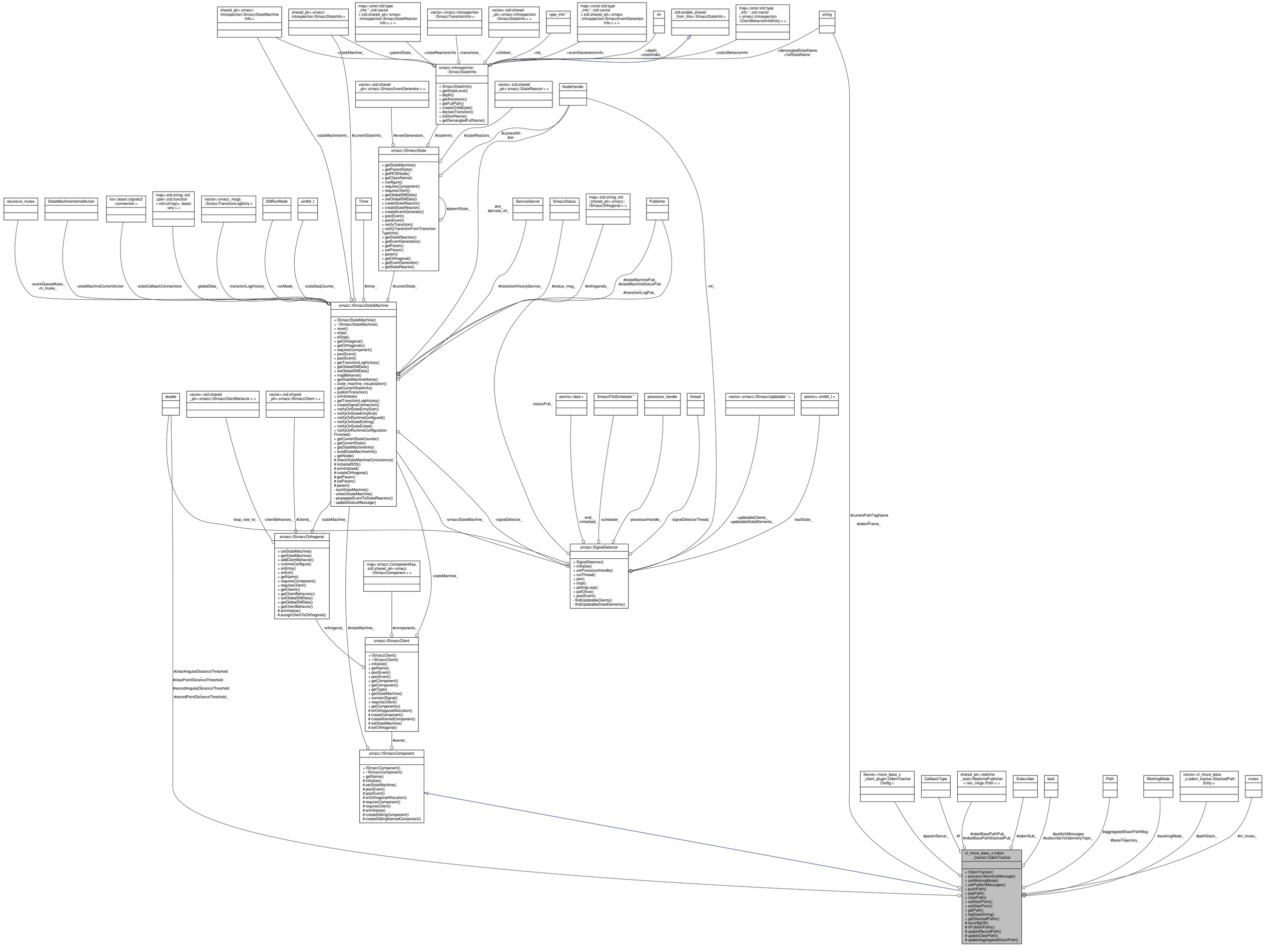
shared_ptr< smacc::introspection::SmaccStateMachineInfo >
shared_ptr< smacc::introspection::SmaccStateInfo >
map< const std::type_info *, std::vector< std::shared_ptr< smacc::introspection::SmaccStateReactorInfo > > >
vector< smacc::introspection::SmaccTransitionInfo >
vector< std::shared_ptr< smacc::introspection::SmaccStateInfo > >
type_info *
map< const std::type_info *, std::vector< std::shared_ptr< smacc::introspection::SmaccEventGeneratorInfo > > >
int
std::enable_shared_from_this< SmaccStateInfo >
map< const std::type_info *, std::vector< smacc::introspection::ClientBehaviorInfoEntry > >
string
+stateMachine_
+parentState_
+stateReactorsInfo
+transitions_
+children_
+tid_
+eventGeneratorsInfo
+depth_
+stateIndex_
+staticBehaviorInfo
+demangledStateName
+fullStateName
smacc::introspection::SmaccStateInfo
+ SmaccStateInfo()
+ getStateLevel()
+ depth()
+ getAncestors()
+ getFullPath()
+ createChildState()
+ declareTransition()
+ toShortName()
+ getDemangledFullName()
vector< std::shared_ptr< smacc::SmaccEventGenerator > >
vector< std::shared_ptr< smacc::StateReactor > >
NodeHandle
-stateMachineInfo_
#currentStateInfo_
#eventGenerators_
#stateInfo_
#stateReactors_
#contextNh
#nh
smacc::ISmaccState
+ getStateMachine()
+ getParentState()
+ getROSNode()
+ getClassName()
+ configure()
+ requiresComponent()
+ requiresClient()
+ getGlobalSMData()
+ setGlobalSMData()
+ createStateReactor()
+ createStateReactor()
+ createEventGenerator()
+ postEvent()
+ postEvent()
+ notifyTransition()
+ notifyTransitionFromTransitionTypeInfo()
+ getStateReactors()
+ getEventGenerators()
+ getParam()
+ setParam()
+ param()
+ getOrthogonal()
+ getEventGenerator()
+ getStateReactor()
#parentState_
recursive_mutex
StateMachineInternalAction
list< boost::signals2::connection >
map< std::string, std::pair< std::function< std::string()>, boost::any > >
vector< smacc_msgs::SmaccTransitionLogEntry >
SMRunMode
uint64_t
Timer
#nh_
#private_nh_
ServiceServer
SmaccStatus
map< std::string, std::shared_ptr< smacc::ISmaccOrthogonal > >
Publisher
-eventQueueMutex_
-m_mutex_
-stateMachineCurrentAction
-stateCallbackConnections
-globalData_
-transitionLogHistory_
-runMode_
-stateSeqCounter_
#timer_
#currentState_
#transitionHistoryService_
#status_msg_
#orthogonals_
#stateMachinePub
#stateMachineStatusPub
#transitionLogPub_
-nh_
smacc::ISmaccStateMachine
+ ISmaccStateMachine()
+ ~ISmaccStateMachine()
+ reset()
+ stop()
+ eStop()
+ getOrthogonal()
+ getOrthogonals()
+ requiresComponent()
+ postEvent()
+ postEvent()
+ getTransitionLogHistory()
+ getGlobalSMData()
+ setGlobalSMData()
+ mapBehavior()
+ getStateMachineName()
+ state_machine_visualization()
+ getCurrentStateInfo()
+ publishTransition()
+ onInitialize()
+ getTransitionLogHistory()
+ createSignalConnection()
+ notifyOnStateEntryStart()
+ notifyOnStateEntryEnd()
+ notifyOnRuntimeConfigured()
+ notifyOnStateExitting()
+ notifyOnStateExited()
+ notifyOnRuntimeConfigurationFinished()
+ getCurrentStateCounter()
+ getCurrentState()
+ getStateMachineInfo()
+ buildStateMachineInfo()
+ getNode()
# checkStateMachineConsistence()
# initializeROS()
# onInitialized()
# createOrthogonal()
# getParam()
# setParam()
# param()
- lockStateMachine()
- unlockStateMachine()
- propagateEventToStateReactors()
- updateStatusMessage()
double
vector< std::shared_ptr< smacc::ISmaccClientBehavior > >
vector< std::shared_ptr< smacc::ISmaccClient > >
-statusPub_
atomic< bool >
SmaccFifoScheduler *
processor_handle
thread
vector< smacc::ISmaccUpdatable * >
atomic< uint64_t >
-loop_rate_hz
-clientBehaviors_
#clients_
-stateMachine_
-smaccStateMachine_
-signalDetector_
-end_
-initialized_
-scheduler_
-processorHandle_
-signalDetectorThread_
-updatableClients_
-updatableStateElements_
-lastState_
#currentPathTagName
#odomFrame_
smacc::ISmaccOrthogonal
+ setStateMachine()
+ getStateMachine()
+ addClientBehavior()
+ runtimeConfigure()
+ onEntry()
+ onExit()
+ getName()
+ requiresComponent()
+ requiresClient()
+ getClients()
+ getClientBehaviors()
+ setGlobalSMData()
+ getGlobalSMData()
+ getClientBehavior()
# onInitialize()
# assignClientToOrthogonal()
map< smacc::ComponentKey, std::shared_ptr< smacc::ISmaccComponent > >
smacc::SignalDetector
+ SignalDetector()
+ initialize()
+ setProcessorHandle()
+ runThread()
+ join()
+ stop()
+ pollingLoop()
+ pollOnce()
+ postEvent()
- findUpdatableClients()
- findUpdatableStateElements()
-orthogonal_
#stateMachine_
#components_
smacc::ISmaccClient
+ ISmaccClient()
+ ~ISmaccClient()
+ initialize()
+ getName()
+ postEvent()
+ postEvent()
+ getComponent()
+ getComponent()
+ getType()
+ getStateMachine()
+ connectSignal()
+ requiresClient()
+ getComponents()
# onOrthogonalAllocation()
# createComponent()
# createNamedComponent()
# setStateMachine()
# setOrthogonal()
#owner_
smacc::ISmaccComponent
+ ISmaccComponent()
+ ~ISmaccComponent()
+ getName()
# initialize()
# setStateMachine()
# postEvent()
# postEvent()
# onOrthogonalAllocation()
# requiresComponent()
# requiresClient()
# onInitialize()
# createSiblingComponent()
# createSiblingNamedComponent()
#clearAngularDistanceThreshold
#clearPointDistanceThreshold
#recordAngularDistanceThreshold
#recordPointDistanceThreshold_
Server< move_base_z_client_plugin::OdomTrackerConfig >
CallbackType
shared_ptr< realtime_tools::RealtimePublisher< nav_msgs::Path > >
Subscriber
bool
Path
WorkingMode
vector< cl_move_base_z::odom_tracker::StackedPathEntry >
mutex
#paramServer_
#f
#robotBasePathPub_
#robotBasePathStackedPub_
#odomSub_
#publishMessages
#subscriboToOdometryTopic_
#aggregatedStackPathMsg
#baseTrajectory_
#workingMode_
#pathStack_
#m_mutex_
cl_move_base_z::odom_tracker::OdomTracker
+ OdomTracker()
+ processOdometryMessage()
+ setWorkingMode()
+ setPublishMessages()
+ pushPath()
+ popPath()
+ clearPath()
+ setStartPoint()
+ setStartPoint()
+ getPath()
+ logStateString()
+ getStackedPaths()
# reconfigCB()
# rtPublishPaths()
# updateRecordPath()
# updateClearPath()
# updateAggregatedStackPath()