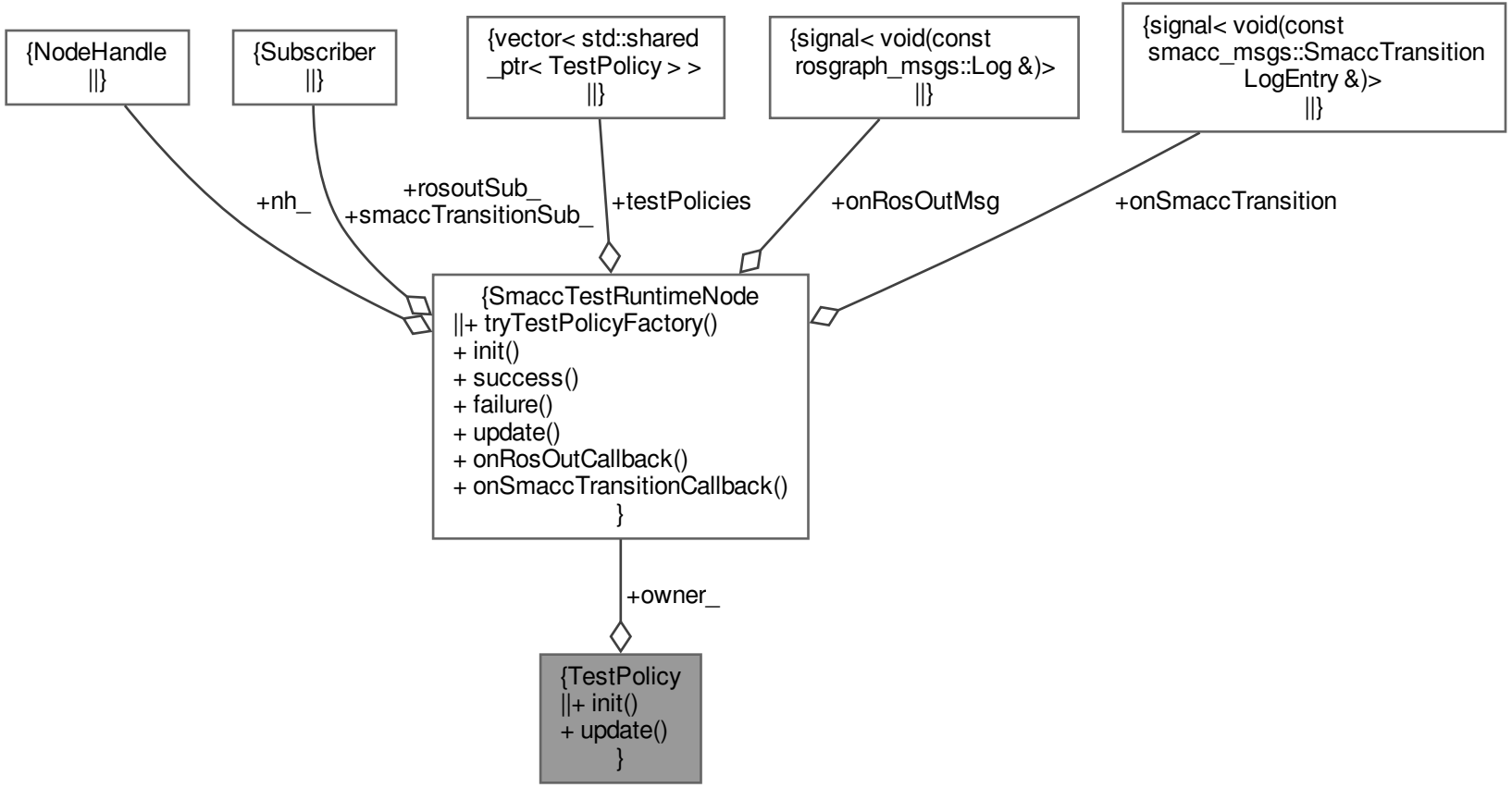
{NodeHandle
||}
{Subscriber
||}
{vector< std::shared
_ptr< TestPolicy > >
||}
{signal< void(const
rosgraph_msgs::Log &)>
||}
{signal< void(const
smacc_msgs::SmaccTransition
LogEntry &)>
||}
+nh_
+rosoutSub_
+smaccTransitionSub_
+testPolicies
+onRosOutMsg
+onSmaccTransition
{SmaccTestRuntimeNode
||+ tryTestPolicyFactory()
+ init()
+ success()
+ failure()
+ update()
+ onRosOutCallback()
+ onSmaccTransitionCallback()
}
+owner_
{TestPolicy
||+ init()
+ update()
}