

oroGen Cheat Sheet

oroGen v2.x / sheet v1.0

Main Scope

Task Definitions

Typography:

description, **oroGen specification**, C++ code

Project Information

General oroGen project information
name "project_name"
version "0.1"

Types

oroGen can use C++ types ...

From a C++ library that exports
a pkg-config file

```
using_library "pkg_name"  
import_types_from "header_file.h"
```

From a local C++ header

```
import_types_from "header_file.h"
```

From another oroGen project

```
import_types_from "project_name"
```

Tasks

```
task_context "ClassName" do  
  # task definition statements  
end
```

Defines a subclass of RTT::TaskContext

```
project_name::ClassName
```

It is defined in

```
tasks/ClassName.hpp and  
tasks/ClassName.cpp
```

Deployments

```
deployment "name" do  
  # deployment statements  
end
```

Generates a corresponding binary
which deploys the specified tasks

Properties

```
property('name', 'type::Name')  
property('name', 'type::Name', def_value)  
  
// Read the property  
type::Name sample = _name.get();  
// Write the property  
_name.set(sample);
```

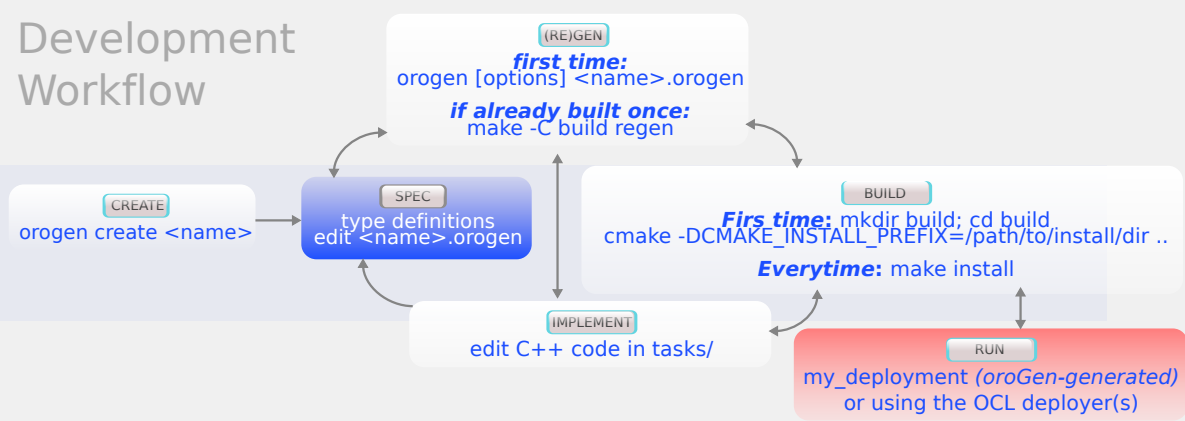
Input Ports

```
input_port('name', 'type::Name')  
  
type::Name sample;  
if (_name.read(sample) != RTT::NoData)  
{  
  // there either a new, or an already-read  
  // sample on _name.  
}  
if (_name.read(sample) == RTT::NewData)  
{  
  // there was a never-read sample  
  // on _name  
}  
if (_name.connected())  
{  
  // do something only if the port  
  // is connected  
}
```

Output Ports

```
output_port('name', 'type::Name')  
  
type::Name sample;  
// write data into 'sample'  
_name.write(sample);  
  
if (_name.connected())  
{  
  // do something only if the port  
  // is connected  
}
```

Development Workflow



State Machine

needs_configuration

The task context starts in PRE_OPERATIONAL,
i.e. configureHook() has to be called

Sub-states of RUNNING

```
runtime_states 'diving', 'searching'  
runtime(diving)
```

Sub-states of RUNTIME_ERROR

```
error_states 'heat_throttling', 'self_test'  
error(heat_throttling)
```

Sub-states of EXCEPTION

```
exception_states 'io_error', 'com_error'  
exception(com_error)
```

Sub-states of FATAL_ERROR

```
fatal_states 'internal_error'  
fatal(internal_error)
```

Triggering

(works hand-in-hand with deployments)

Port-driven tasks

This can be combined with fd_driven and triggered activities,
but won't work on periodic activities

port_driven

Task will be triggered when data arrives on
all input ports declared before the statement

```
port_driven 'port_name'[, 'port_name']
```

Task will be triggered when data arrives on
the specified input ports

Default and required activities

'policy_type' can be either 'triggered', 'fd_driven' or 'periodic'.
In the case of 'periodic', policy_options is the period in seconds

```
default_activity policy_type[, policy_options]
```

This triggering mechanism will be used if none
is specified in the deployment.

```
required_activity policy_type[, policy_options]
```

This triggering mechanism has to be used.

Deployments

```
task = task('name', 'project::Task')
```

Adds a new task instance of type project::Task
using its default activity type

```
task.periodic(0.1)
```

```
task.fd_driven
```

```
task.triggered
```

Overrides the activity of a deployed task

```
task.realtime
```

Places a deployed task in the OS realtime domain

```
task.priority(value)
```

```
task.highest_priority
```

Sets the priority of the deployed task. **value** is an
integer between 0 and 99. It is only valid for realtime
tasks.

IO-Driven tasks

```
fd_driven
```

Task will be triggered when data arrives on
some file descriptors.

Must be set up (usually in configureHook) with
RTT::extras::FileDescriptorActivity* fd_activity =
getActivity<RTT::extras::FileDescriptorActivity>();
fd_activity->watch(fd1);
fd_activity->watch(fd2);
fd_activity->watch(fd3);
fd_activity->setTimeout(value_in_ms);

Then, in updateHook()

```
RTT::extras::FileDescriptorActivity* fd_activity =  
getActivity<RTT::extras::FileDescriptorActivity>();  
fd_activity->hasTimeout() // one FD has timeout  
fd_activity->hasError() // one FD has error  
fd_activity->isUpdated(fd1) // fd1 has data on it
```