

Robotics Service Bus - Tasks #1104

Re-enable use auf cause vector

07/30/2012 03:01 PM - J. Wienke

| | | | |
|---|-----------|------------------------|------------|
| Status: | Resolved | Start date: | 10/06/2011 |
| Priority: | Normal | Due date: | |
| Assignee: | | % Done: | 100% |
| Category: | C++ Tools | Estimated time: | 0.00 hour |
| Target version: | | | |
| Description | | | |
| <p>Currently not possible due to restrictions of the handler.</p> <p>One idea could be to let the handler expose a factory function for the event instance to fill and then the strategies can add causes and data before passing the event to the handler again.</p> | | | |

History

#1 - 07/30/2012 03:01 PM - J. Wienke

Moved from old timesync project to be part of the overall rsb project. timesync seems to be quite essential for some use cases with RSB. Hence we moved it to the main project as a tool.