

Robotics Service Bus - Bug #1552

Catching exceptions caused by failed socket transport initialization leads to crash

06/26/2013 04:28 PM - J. Moringen

Status:	Resolved	Start date:	06/26/2013
Priority:	Normal	Due date:	
Assignee:	J. Moringen	% Done:	100%
Category:	C++	Estimated time:	0.00 hour
Target version:	rsb-0.9		

Description

```
#include <rsb/Factory.h>
```

```
int main() {  
    // first get a factory instance that is used to create RSB domain objects  
    rsb::Factory &factory = rsb::getFactory();  
    try {  
        // set up the scope to receive on either from the command line argument or  
        // use the default scope of the informer example  
        rsb::Scope scope = rsb::Scope("/dummy");  
  
        // create a listener that asynchronously receives events from the bus and  
        // dispatches them to registered handlers  
        rsb::ListenerPtr listener=factory.createListener(scope);  
    }  
    catch(...) {  
        ;  
    }  
}
```

rsb.conf:

```
[qualityofservice]  
reliability = UNRELIABLE  
ordering = UNORDERED
```

```
[errorhandling]  
onhandlererror = LOG
```

```
[transport.socket]  
host = vitellius  
port = 55555  
enabled = 1 # this is the default  
server=0
```

```
[transport.socket.converter]  
image = lplImage # wireSchema = dataType
```

```
[transport.inprocess]  
foo = barbar  
factor = 1.5  
enabled = 0
```

```
g++ weird_try_catch.cpp -I /media/local/hriechma/rsb/include/rsb0.9/ -I /media/local/hriechma/rsb/include/rsb0.9/ -L /media/local/hriechma/rsb/lib/ -l:librsb.so.0.9 -l:librsc0.9.so.0.9 -lboost_system
```

Ergebnis ist das beim Ausführen diese Ausgabe kommt:

```
a.out: /usr/include/boost/smart_ptr/shared_ptr.hpp:418: T* boost::shared_ptr<T>::operator->() const [with T = rsb::transport::socket::Bus]: Assertion `px != 0' failed.  
Aborted
```

Wenn man das trycatch weglässt, kommt ein `std::runtime_error` dass er nicht verbinden konnte. Mit dem trycatch würde ich erwarten, dass gar keine Ausgabe kommt und das Programm sauber beendet wird.

Associated revisions

Revision [fda3b25a](#) - 07/01/2013 04:57 PM - J. Moringen

Fixed shared pointer deref in `src/rsb/transport/socket/*Connector*.cpp`

fixes #1552

- `src/rsb/transport/socket/ConnectorBase.cpp` (header): updated copyright
(`ConnectorBase::deactivate`): check Bus shared_ptr before dereferencing
- `src/rsb/transport/socket/InConnector.cpp` (header): updated copyright
(`InConnector::deactivate`): check Bus shared_ptr before dereferencing
- `test/rsbtest_toplevel_catch.cpp`: new file; contains body of `toplevel_catch` test
- `CMakeLists.txt`: added `TOPLEVEL_CATCH_TEST_NAME`
- `test/CMakeLists.txt`: added new test `toplevel_catch`

History

#1 - 07/01/2013 04:46 PM - J. Moringen

- Status changed from *New* to *In Progress*
- % Done changed from 0 to 30

#2 - 07/01/2013 04:46 PM - J. Moringen

- Assignee set to J. Moringen

#3 - 07/01/2013 06:30 PM - J. Moringen

- Status changed from *In Progress* to *Resolved*
- % Done changed from 30 to 100

Applied in changeset `rsb-cpp|commit:fda3b25ab6b0ad36935b703f84164ef5db5732a6`.