

## Robotics Service Bus - Tasks #263

### Implement coherent dynamic behavior

04/28/2011 05:34 PM - J. Wienke

<b>Status:</b> Resolved	<b>Start date:</b> 04/28/2011
<b>Priority:</b> Normal	<b>Due date:</b>
<b>Assignee:</b>	<b>% Done:</b> 100%
<b>Category:</b> C++	<b>Estimated time:</b> 7.00 hours
<b>Target version:</b>	
<b>Description</b>	
According to [[Guarantees]]	
<b>Subtasks:</b>	
Tasks # 264: Adapt handling of incoming events	<b>Resolved</b>
Tasks # 267: Fix (re)configuration of filters and handlers	<b>Resolved</b>

#### Associated revisions

##### Revision 310e62f7 - 05/02/2011 05:56 AM - J. Moringen

Allow InRouteConfigurator to manage multiple connectors

refs #263

- src/rsb/Listener.cpp: add multiple connectors to configurator instead of asserting `connectors.size() == 1`
- src/rsb/eventprocessing/InRouteConfigurator.{h,cpp}: maintain a list of connectors instead of a single connector; loop over connectors when necessary
- test/rsb/RSBTest.cpp: adapted to changed configurator interface

##### Revision 7d3078bd - 05/02/2011 06:11 AM - J. Moringen

Allow OutRouteConfigurator to manage multiple connectors

refs #263

- src/rsb/Informer.cpp: add multiple connectors to configurator instead of asserting `connectors.size() == 1`
- src/rsb/eventprocessing/OutRouteConfigurator.{h,cpp}: maintain a list of connectors instead of a single connector; loop over connectors when necessary
- test/rsb/RSBTest.cpp: adapted to changed configurator interface

#### History

##### #1 - 04/28/2011 08:37 PM - J. Moringen

- Subject changed from *Implment coherent dynamic behavior* to *Implement coherent dynamic behavior*

##### #2 - 05/02/2011 06:11 AM - J. Moringen

- Status changed from *New* to *In Progress*

##### #3 - 05/03/2011 01:46 PM - J. Wienke

- Status changed from *In Progress* to *Resolved*