smacc::ISmaccClientBehavior

- stateMachine_
- currentState
- currentOrthogonal

+ ISmaccClientBehavior()
+ ~ISmaccClientBehavior()
+ getStateMachine()
+ getName()
+ requiresClient()
+ requiresComponent()
+ getNode()
# runtimeConfigure()
# onEntry()
# onExit()
# postEvent()
# postEvent()
# getCurrentState()
# executeOnEntry()
# executeOnExit()
# dispose()
- onOrthogonalAllocation()

smacc::SmaccAsyncClientBehavior

- onEntryThread_
- onExitThread_
- postFinishEventFn_
- postSuccessEventFn_
- postFailureEventFn_
- onFinished_
- onSuccess_
- onFailure_

+ onOrthogonalAllocation()
+ ~SmaccAsyncClientBehavior()
+ onSuccess()
+ onFinished()
+ onFailure()
# executeOnEntry()
# executeOnExit()
# postSuccessEvent()
# postFailureEvent()
# dispose()

smacc::SmaccClientBehavior

+ onEntry()
+ onExit()

cl_move_base_z::CbMoveBase
ClientBehaviorBase

# moveBaseClient_
# visualizationMarkersPub_

+ onOrthogonalAllocation()
- propagateSuccessEvent()
- propagateFailureEvent()

cl_move_group_interface
::CbMoveCartesianRelative

+ offset_
+ scalingFactor_
+ group_
+ moveGroupSmaccClient_

+ CbMoveCartesianRelative()
+ CbMoveCartesianRelative()
+ onEntry()
+ onExit()
+ moveRelativeCartesian()

cl_move_group_interface
::CbMoveEndEffector

+ targetPose
+ tip_link_
+ group_
# movegroupClient_

+ CbMoveEndEffector()
+ CbMoveEndEffector()
+ onEntry()
# moveToAbsolutePose()

cl_move_group_interface
::CbMoveEndEffectorRelative

+ transform_
+ group_
# movegroupClient_

+ CbMoveEndEffectorRelative()
+ CbMoveEndEffectorRelative()
+ onEntry()
+ onExit()
# moveRelative()

cl_move_group_interface
::CbMoveEndEffectorTrajectory

+ group_
+ tipLink_
+ allowInitialTrajectoryState
JointDiscontinuity_
# endEffectorTrajectory_
# movegroupClient_
# beahiorMarkers_
- markersPub_
- markersInitialized_
- iksrv_
- m_mutex_
- postJointDiscontinuityEvent
- postIncorrectInitialState
Event

- postMotionExecutionFailure
Events
- autocleanmarkers

+ CbMoveEndEffectorTrajectory()
+ CbMoveEndEffectorTrajectory()
+ onOrthogonalAllocation()
+ onEntry()
+ onExit()
+ update()
# computeJointSpaceTrajectory()
# executeJointSpaceTrajectory()
# generateTrajectory()
# createMarkers()
# getCurrentEndEffectorPose()
- initializeROS()

cl_move_group_interface
::CbMoveJoints

+ scalingFactor_
+ jointValueTarget_
+ group_
# movegroupClient_

+ CbMoveJoints()
+ CbMoveJoints()
+ onEntry()
+ onExit()
# moveJoints()

cl_move_group_interface
::CbMoveNamedTarget

# movegroupClient_
# namedTarget_

+ CbMoveNamedTarget()
+ onEntry()
+ onExit()
+ getNamedTargetValues()

cl_move_base_z::CbAbsolute
Rotate

+ listener
+ absoluteGoalAngleDegree
+ yawGoalTolerance
+ maxVelTheta
+ spinningPlanner
- oldYawTolerance
- oldMaxVelTheta
- oldMinVelTheta

+ CbAbsoluteRotate()
+ CbAbsoluteRotate()
+ onEntry()
+ onExit()
- updateTemporalBehaviorParameters()

cl_move_base_z::CbNavigate
Backwards

+ backwardDistance
+ backwardSpeed
+ listener
+ odomTracker_

+ CbNavigateBackwards()
+ CbNavigateBackwards()
+ onEntry()
+ onExit()

cl_move_base_z::CbNavigate
Forward

+ forwardDistance
+ forwardSpeed
+ forceInitialOrientation
+ listener
+ odomTracker_

+ CbNavigateForward()
+ CbNavigateForward()
+ onEntry()
+ onExit()

cl_move_base_z::CbNavigate
GlobalPosition

+ goalPosition
+ goalYaw

+ CbNavigateGlobalPosition()
+ CbNavigateGlobalPosition()
+ setGoal()
+ onEntry()
+ execute()
+ readStartPoseFromParameter
Server()
+ onExit()

cl_move_base_z::CbNavigate
NextWaypoint

+ CbNavigateNextWaypoint()
+ ~CbNavigateNextWaypoint()
+ onEntry()
+ onExit()

cl_move_base_z::CbRotate

+ listener
+ rotateDegree

+ CbRotate()
+ CbRotate()
+ onEntry()

cl_move_base_z::CbUndoPath
Backwards

+ forceUndoLocalPlanner
- listener

+ onEntry()
+ onExit()

cl_move_base_z::CbUndoPath
Backwards2

- goal_
- odomTracker_
- listener
- robotPose_
- goalLinePassed_
- initial_plane_side_
- triggerThreshold_
- postVirtualLinePassed_

+ CbUndoPathBackwards2()
+ onEntry()
+ onExit()
+ update()
+ onOrthogonalAllocation()
- publishMarkers()
- evalPlaneSide()

cl_move_group_interface
::CbCircularPivotMotion

+ angularSpeed_rad_s_
+ linearSpeed_m_s_
+ relativeInitialPose_
# planePivotPose_
# deltaRadians_

+ CbCircularPivotMotion()
+ CbCircularPivotMotion()
+ CbCircularPivotMotion()
+ generateTrajectory()
+ createMarkers()
- computeCurrentEndEffector
PoseRelativeToPivot()

cl_move_group_interface
::CbCircularPouringMotion

+ angularSpeed_rad_s_
+ linearSpeed_m_s_
+ directionVector_
+ pointerRelativePose_
# relativePivotPoint_
# deltaHeight_
# pointerTrajectory_
- globalFrame_

+ CbCircularPouringMotion()
+ generateTrajectory()
+ createMarkers()
- computeCurrentEndEffector
PoseRelativeToPivot()

cl_move_group_interface
::CbExecuteLastTrajectory

+ CbExecuteLastTrajectory()
+ ~CbExecuteLastTrajectory()
+ onEntry()

cl_move_group_interface
::CbMoveCartesianRelative2

+ offset_
+ linearSpeed_m_s_
- globalFrame_

+ CbMoveCartesianRelative2()
+ CbMoveCartesianRelative2()
+ generateTrajectory()

cl_move_group_interface
::CbUndoLastTrajectory

- backIndex_
- trajectory
- reversed

+ CbUndoLastTrajectory()
+ CbUndoLastTrajectory()
+ ~CbUndoLastTrajectory()
+ onEntry()

cl_move_group_interface
::CbEndEffectorRotate

+ CbEndEffectorRotate()
+ ~CbEndEffectorRotate()
+ onEntry()

cl_move_group_interface
::CbMoveKnownState

+ CbMoveKnownState()
+ ~CbMoveKnownState()
- loadJointStatesFromFile()

cl_move_group_interface
::CbMoveLastTrajectoryInitialState

- backIndex_

+ CbMoveLastTrajectoryInitial
State()
+ CbMoveLastTrajectoryInitial
State()
+ ~CbMoveLastTrajectoryInitial
State()
+ onEntry()

cl_multirole_sensor
::CbDefaultMultiRoleSensor
Behavior< ClLidarSensor >

+ sensor_
+ deferedEventPropagation

+ CbDefaultMultiRoleSensor
Behavior()
+ onOrthogonalAllocation()
+ propagateEvent()
+ propagateEvent2()
+ onEntry()
+ onExit()
+ onMessageCallback()
+ getEventLabel()

cl_multirole_sensor
::CbDefaultMultiRoleSensor
Behavior< ClTemperatureSensor >

+ sensor_
+ deferedEventPropagation

+ CbDefaultMultiRoleSensor
Behavior()
+ onOrthogonalAllocation()
+ propagateEvent()
+ propagateEvent2()
+ onEntry()
+ onExit()
+ onMessageCallback()
+ getEventLabel()

cl_multirole_sensor
::CbDefaultMultiRoleSensor
Behavior< sm_dance_bot_strikes
_ back::cl_lidar::ClLidarSensor >

+ sensor_
+ deferedEventPropagation

+ CbDefaultMultiRoleSensor
Behavior()
+ onOrthogonalAllocation()
+ propagateEvent()
+ propagateEvent2()
+ onEntry()
+ onExit()
+ onMessageCallback()
+ getEventLabel()

smacc::CbSubscriptionCallback
Base< std_msgs::UInt16 >

# attachedClient_

+ onEntry()
+ onMessageReceived()

cl_keyboard::CbDefaultKeyboard
Behavior

+ ClKeyboard_
+ postEventKeyPress

+ onEntry()
+ onOrthogonalAllocation()
+ OnKeyPress()
+ postKeyEvent()

cl_move_group_interface
::CbAttachObject

+ targetObjectName_

+ CbAttachObject()
+ CbAttachObject()
+ onEntry()
+ onExit()

cl_move_group_interface
::CbDetachObject

+ onEntry()
+ onExit()

cl_multirole_sensor
::CbDefaultMultiRoleSensor
Behavior< ClientType >

+ sensor_
+ deferedEventPropagation

+ CbDefaultMultiRoleSensor
Behavior()
+ onOrthogonalAllocation()
+ propagateEvent()
+ propagateEvent2()
+ onEntry()
+ onExit()
+ onMessageCallback()
+ getEventLabel()

cl_ros_publisher::CbDefault
PublishLoop

- deferedPublishFn
- client_

+ CbDefaultPublishLoop()
+ CbDefaultPublishLoop()
+ setMessage()
+ onEntry()
+ update()
+ onExit()

cl_ros_publisher::CbMuted
Behavior< RosMsgType >

+ onEntry()
+ onExit()

cl_ros_publisher::CbPublish
Once< RosMsgType >

- deferedPublishFn
- client_

+ CbPublishOnce()
+ CbPublishOnce()
+ setMessage()
+ onEntry()
+ onExit()

cl_ros_timer::CbTimer

- timerClient_
- postTimerEvent_
- c_

+ onEntry()
+ onExit()
+ onOrthogonalAllocation()
+ onClientTimerTickCallback()

cl_ros_timer::CbTimerCountdownLoop

- tickCounter_
- tickTriggerCount_
- timerClient_
- postCountDownEvent_
- onTimerTick_

+ CbTimerCountdownLoop()
+ onEntry()
+ onExit()
+ onOrthogonalAllocation()
+ onTimerTick()
- onClientTimerTickCallback()

cl_ros_timer::CbTimerCountdownOnce

- tickCounter_
- tickTriggerCount_
- timerClient_
- postCountDownEvent_
- onTimerTick_

+ CbTimerCountdownOnce()
+ onEntry()
+ onExit()
+ onOrthogonalAllocation()
+ onTimerTick()
- onClientTimerTickCallback()

sm_calendar_week::cl
_subscriber::CbDefaultSubscriber
Behavior

+ onEntry()

sm_calendar_week::cl
_subscriber::CbWatchdogSubscriber
Behavior

+ onEntry()

sm_dance_bot::cl_led
::CbLEDOff

+ ledActionClient_

+ onEntry()
+ onExit()

sm_dance_bot::cl_led
::CbLEDOn

+ ledActionClient_

+ onEntry()
+ onExit()

sm_dance_bot::cl_service3
::CbService3

- serviceClient_
- value_

+ CbService3()
+ onEntry()

sm_dance_bot::cl_string
_ publisher::CbStringPublisher

+ publisherClient_
+ msg_

+ CbStringPublisher()
+ onEntry()
+ onExit()

sm_dance_bot_2::cl
_ led::CbLEDOff

+ ledActionClient_

+ onEntry()
+ onExit()

sm_dance_bot_2::cl
_ led::CbLEDOn

+ ledActionClient_

+ onEntry()
+ onExit()

sm_dance_bot_2::cl
_service3::CbService3

- serviceClient_
- value_

+ CbService3()
+ onEntry()

sm_dance_bot_2::cl
_string_publisher::CbString
Publisher

+ publisherClient_
+ msg_

+ CbStringPublisher()
+ onEntry()
+ onExit()

sm_dance_bot_strikes
_ back::cl_led::CbLEDOff

+ ledActionClient_

+ onEntry()
+ onExit()

sm_dance_bot_strikes
_ back::cl_led::CbLEDOn

+ ledActionClient_

+ onEntry()
+ onExit()

sm_dance_bot_strikes
_ back::cl_service3::CbService3

- serviceClient_
- value_

+ CbService3()
+ onEntry()

sm_dance_bot_strikes
_ back::cl_string_publisher
::CbStringPublisher

+ publisherClient_
+ msg_

+ CbStringPublisher()
+ onEntry()
+ onExit()

sm_ferrari::cl_subscriber
::CbMySubscriberBehavior

+ postMyEvent_

+ onEntry()
+ onOrthogonalAllocation()
+ onMessageReceived()

sm_fetch_screw_loop
_ 1::cl_gripper::CbCloseGripper

+ onEntry()
+ onExit()

sm_fetch_screw_loop
_ 1::cl_gripper::CbOpenGripper

+ onEntry()
+ onExit()

sm_fetch_six_table
_ pick_n_sort_1::cl_gripper
::CbCloseGripper

+ onEntry()
+ onExit()

sm_fetch_six_table
_ pick_n_sort_1::cl_gripper
::CbOpenGripper

+ onEntry()
+ onExit()

sm_fetch_two_table
_ pick_n_place_1::cl
_gripper::CbCloseGripper

+ onEntry()
+ onExit()

sm_fetch_two_table
_ pick_n_place_1::cl
_gripper::CbOpenGripper

+ onEntry()
+ onExit()

sm_fetch_two_table
_whiskey_pour::cl_gripper
::CbCloseGripper

+ onEntry()
+ onExit()

sm_fetch_two_table
_whiskey_pour::cl_gripper
::CbOpenGripper

+ onEntry()
+ onExit()

sm_packml::cl_subscriber
::CbDefaultSubscriberBehavior

+ onEntry()

sm_packml::cl_subscriber
::CbWatchdogSubscriberBehavior

+ onEntry()

sm_respira_1::cl_subscriber
::CbDefaultSubscriberBehavior

+ onEntry()

sm_respira_1::cl_subscriber
::CbWatchdogSubscriberBehavior

+ onEntry()

sm_starcraft_ai::cl
_subscriber::CbDefaultSubscriber
Behavior

+ onEntry()

sm_starcraft_ai::cl
_subscriber::CbWatchdogSubscriber
Behavior

+ onEntry()

sm_three_some::cl_subscriber
::CbDefaultSubscriberBehavior

+ onEntry()

sm_three_some::cl_subscriber
::CbWatchdogSubscriberBehavior

+ onEntry()

smacc::CbSubscriptionCallback
Base< TMsg >

# attachedClient_

+ onEntry()
+ onMessageReceived()

sm_dance_bot::cl_lidar
::CbLidarSensor

+ CbLidarSensor()
+ onEntry()
+ onMessageCallback()

sm_dance_bot_2::cl
_ lidar::CbLidarSensor

+ CbLidarSensor()
+ onEntry()
+ onMessageCallback()

sm_dance_bot::cl_temperature
_sensor::CbConditionTemperatureSensor

+ CbConditionTemperatureSensor()
+ onMessageCallback()

sm_dance_bot_2::cl
_temperature_sensor
::CbConditionTemperatureSensor

+ CbConditionTemperatureSensor()
+ onMessageCallback()

sm_dance_bot_strikes
_ back::cl_temperature
_sensor::CbConditionTemperature
Sensor

+ CbConditionTemperatureSensor()
+ onMessageCallback()

sm_dance_bot_strikes
_ back::cl_lidar::CbLidarSensor

+ CbLidarSensor()
+ onEntry()
+ onMessageCallback()

sm_subscriber::CbPostCustom
Event

+ postEventImportantMessage

+ onMessageReceived()
+ onOrthogonalAllocation()

sm_subscriber::CbPrintMessage
Number

+ onMessageReceived()

< ClLidarSensor > < ClTemperatureSensor > < sm_dance_bot_strikes

_ back::cl_lidar::ClLidarSensor > < std_msgs::UInt16 >