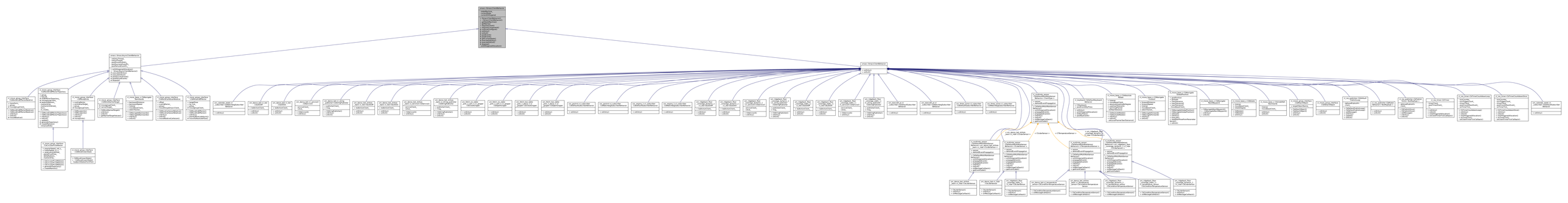

smacc::ISmaccClientBehavior

- stateMachine_
- currentState
- currentOrthogonal

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

smacc::SmaccAsyncClientBehavior

- onEntryThread_
- onExitThread_
- postFinishEventFn_
- postSuccessEventFn_
- postFailureEventFn_

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

smacc::SmaccClientBehavior

+ onEntry()
+ onExit()

cl_move_base_z::CbNavigate
Backwards

+ backwardDistance
+ backwardSpeed
+ listener
+ moveBaseClient_
+ odomTracker_

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

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()
+ planAndExecuteAsync()
# moveToAbsolutePose()

cl_move_group_interface
::CbMoveEndEffectorRelative

+ transform_
+ group_
# movegroupClient_

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

cl_move_group_interface
::CbMoveEndEffectorTrajectory

+ group_
+ tipLink_
# endEffectorTrajectory_
# movegroupClient_
# beahiorMarkers_
- markersPub_
- markersInitialized_
- iksrv_
- m_mutex_

+ CbMoveEndEffectorTrajectory()
+ CbMoveEndEffectorTrajectory()
+ onEntry()
+ onExit()
+ update()
# generateTrajectory()
# createMarkers()
- 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_group_interface
::CbCircularPivotMotion

+ angularSpeed_rad_s_
+ linearSpeed_m_s_
+ relativeInitialPose_
- planePivotPose_
- deltaRadians_
- markersPub_

+ CbCircularPivotMotion()
+ CbCircularPivotMotion()
+ CbCircularPivotMotion()
+ generateTrajectory()
+ createMarkers()

cl_move_group_interface
::CbMoveKnownState

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

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()

cl_multirole_sensor
::CbDefaultMultiRoleSensor
Behavior< sm_ridgeback_floor
_coverage_dynamic_1::cl_lidar
::ClLidarSensor >

+ sensor_
+ deferedEventPropagation

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

cl_keyboard::CbDefaultKeyboard
Behavior

+ ClKeyboard_
+ postEventKeyPress

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

cl_move_base_z::CbAbsolute
Rotate

+ listener
+ moveBaseClient_
+ absoluteGoalAngleDegree
+ yawGoalTolerance
+ spinningPlanner
- oldYawTolerance

+ CbAbsoluteRotate()
+ CbAbsoluteRotate()
+ onEntry()
+ onExit()
- setLocalPlannerYawTolerance()

cl_move_base_z::CbNavigate
Forward

+ forwardDistance
+ forwardSpeed
+ listener
+ moveBaseClient_
+ odomTracker_

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

cl_move_base_z::CbNavigate
GlobalPosition

+ goalPosition
+ goalYaw
+ yawTolerance
+ yawToleranceX
+ yawToleranceY
- moveBaseClient_

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

cl_move_base_z::CbNavigate
NextWaypoint

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

cl_move_base_z::CbRotate

+ listener
+ moveBaseClient_
+ rotateDegree

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

cl_move_base_z::CbUndoPath
Backwards

- listener
- moveBaseClient_

- onEntry()
- onExit()

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_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_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_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_ridgeback_floor
_coverage_dynamic_1
::cl_led::CbLEDOff

+ ledActionClient_

+ onEntry()
+ onExit()

sm_ridgeback_floor
_coverage_dynamic_1
::cl_led::CbLEDOn

+ ledActionClient_

+ onEntry()
+ onExit()

sm_ridgeback_floor
_coverage_dynamic_1
::cl_service3::CbService3

- serviceClient_
- value_

+ CbService3()
+ onEntry()

sm_ridgeback_floor
_coverage_dynamic_1
::cl_string_publisher
::CbStringPublisher

+ publisherClient_
+ msg_

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

sm_ridgeback_floor
_coverage_static_1::
cl_led::CbLEDOff

+ ledActionClient_

+ onEntry()
+ onExit()

sm_ridgeback_floor
_coverage_static_1::
cl_led::CbLEDOn

+ ledActionClient_

+ onEntry()
+ onExit()

sm_ridgeback_floor
_coverage_static_1::
cl_service3::CbService3

- serviceClient_
- value_

+ CbService3()
+ onEntry()

sm_ridgeback_floor
_coverage_static_1::
cl_string_publisher::
CbStringPublisher

+ publisherClient_
+ msg_

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

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()

sm_dance_bot::cl_lidar
::CbLidarSensor

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

sm_ridgeback_floor
_coverage_static_1::
cl_lidar::CbLidarSensor

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

sm_dance_bot::cl_temperature
_sensor::CbConditionTemperatureSensor

+ CbConditionTemperatureSensor()
+ onMessageCallback()

sm_dance_bot_strikes
_ back::cl_temperature
_sensor::CbConditionTemperature
Sensor

+ CbConditionTemperatureSensor()
+ onMessageCallback()

sm_ridgeback_floor
_coverage_dynamic_1
::cl_temperature_sensor
::CbConditionTemperatureSensor

+ CbConditionTemperatureSensor()
+ onMessageCallback()

sm_ridgeback_floor
_coverage_static_1::
cl_temperature_sensor
::CbConditionTemperatureSensor

+ CbConditionTemperatureSensor()
+ onMessageCallback()

sm_dance_bot_strikes
_ back::cl_lidar::CbLidarSensor

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

sm_ridgeback_floor
_coverage_dynamic_1
::cl_lidar::CbLidarSensor

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

< ClLidarSensor > < ClTemperatureSensor > < sm_dance_bot_strikes

_ back::cl_lidar::ClLidarSensor >

< sm_ridgeback_floor
_coverage_dynamic_1::
cl_lidar::ClLidarSensor >