smacc::ISmaccClientBehavior stateMachine_ currentState - currentOrthogonal + ISmaccClientBehavior() + ~ISmaccClientBehavior() + getStateMachine() + getName() + requiresClient() + requiresComponent() # runtimeConfigure() # onEntry() # onExit() # postEvent() # postEvent() # getCurrentState() # executeOnEntry() # executeOnExit() # dispose() onOrthogonalAllocation() Δ smacc::SmaccAsyncClientBehavior onEntryThread_ onExitThread postFinishEventFn postSuccessEventFn_ smacc::ISmaccUpdatable postFailureEventFn_ onFinished_ periodDuration onSuccess_ - lastUpdate onFailure + ISmaccUpdatable() + onOrthogonalAllocation() + ISmaccUpdatable() + ~SmaccAsyncClientBehavior() + executeUpdate() + onSuccess() + setUpdatePeriod() + onFinished() # update() + onFailure() # executeOnEntry() # executeOnExit() # postSuccessEvent() # postFailureEvent() # dispose() cl_move_group_interface ::CbMoveEndEffectorTrajectory + group + tipLink + allowInitialTrajectoryState JointDiscontinuity_ # endEffectorTrajectory_ # movegroupClient_ # beahiorMarkers_ - markersPub markersInitialized_ - iksrv m_mutex postJointDiscontinuityEvent postIncorrectInitialState postMotionExecutionFailure **Events** + CbMoveEndEffectorTrajectory() + CbMoveEndEffectorTrajectory() + onOrthogonalAllocation() + onEntry() + onExit() + update() # computeJointSpaceTrajectory() # executeJointSpaceTrajectory() # generateTrajectory() # createMarkers() initializeROS() 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 ::CbEndEffectorRotate

+ CbEndEffectorRotate()

+ onEntry()