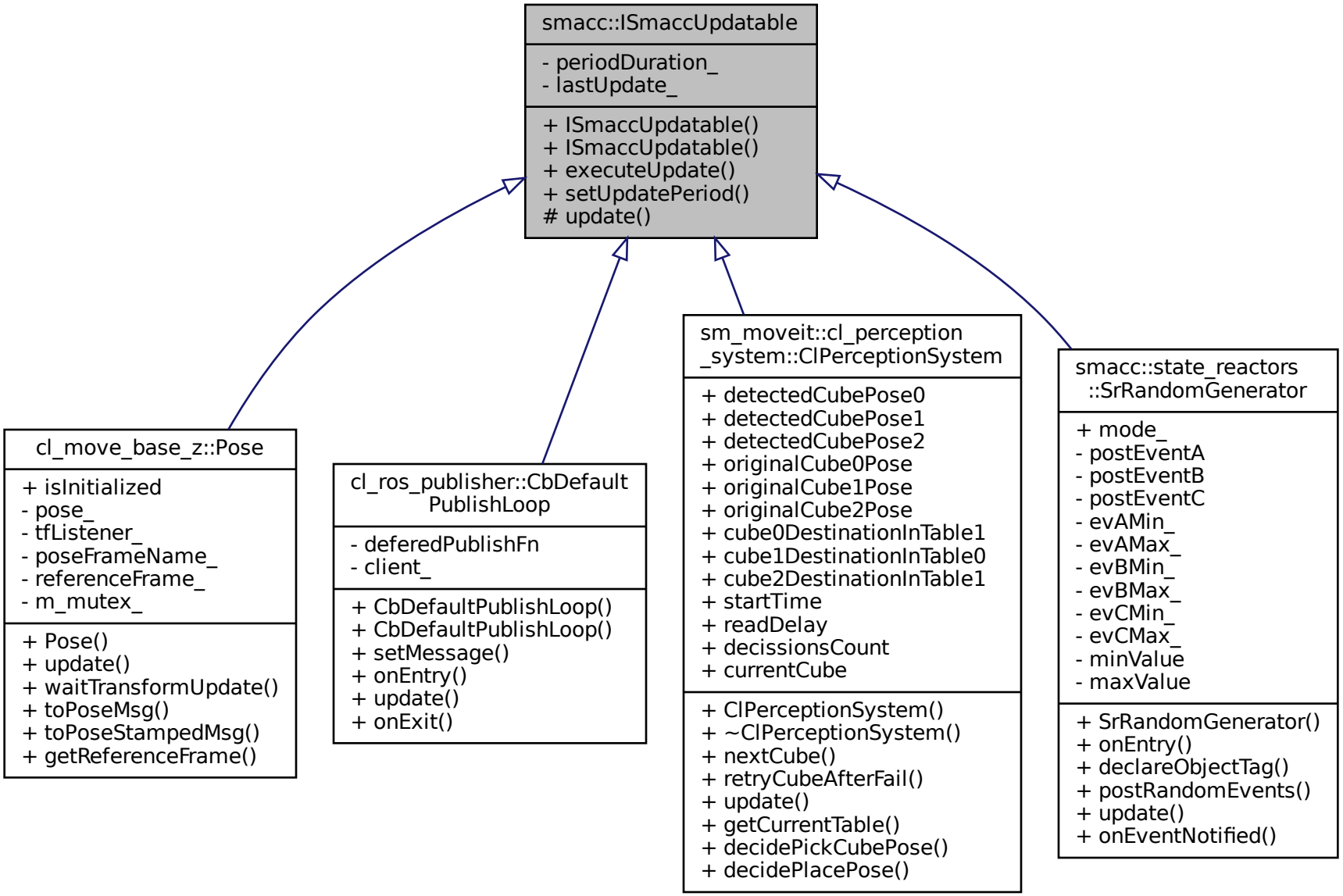
smacc::ISmaccUpdatable
- periodDuration_
- lastUpdate_
+ ISmaccUpdatable()
+ ISmaccUpdatable()
+ executeUpdate()
+ setUpdatePeriod()
# update()
cl_move_base_z::Pose
+ isInitialized
- pose_
- tfListener_
- poseFrameName_
- referenceFrame_
- m_mutex_
+ Pose()
+ update()
+ waitTransformUpdate()
+ toPoseMsg()
+ toPoseStampedMsg()
+ getReferenceFrame()
cl_ros_publisher::CbDefault PublishLoop
- deferedPublishFn
- client_
+ CbDefaultPublishLoop()
+ CbDefaultPublishLoop()
+ setMessage()
+ onEntry()
+ update()
+ onExit()
sm_moveit::cl_perception _system::ClPerceptionSystem
+ detectedCubePose0
+ detectedCubePose1
+ detectedCubePose2
+ originalCube0Pose
+ originalCube1Pose
+ originalCube2Pose
+ cube0DestinationInTable1
+ cube1DestinationInTable0
+ cube2DestinationInTable1
+ startTime
+ readDelay
+ decissionsCount
+ currentCube
+ ClPerceptionSystem()
+ ~ClPerceptionSystem()
+ nextCube()
+ retryCubeAfterFail()
+ update()
+ getCurrentTable()
+ decidePickCubePose()
+ decidePlacePose()
smacc::state_reactors ::SrRandomGenerator
+ mode_
- postEventA
- postEventB
- postEventC
- evAMin_
- evAMax_
- evBMin_
- evBMax_
- evCMin_
- evCMax_
- minValue
- maxValue
+ SrRandomGenerator()
+ onEntry()
+ declareObjectTag()
+ postRandomEvents()
+ update()
+ onEventNotified()