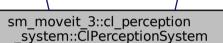## smacc::ISmaccClient

components_
- stateMachine_
- orthogonal_

+ ISmaccClient()
+ ~ISmaccClient()
+ configureEventSourceTypes()
+ initialize()
+ getName()
+ postEvent()
+ postEvent()
+ getComponent()
+ getComponent()
+ getType()
+ getStateMachine()
+ connectSignal()
+ requiresClient()
+ getComponents()
# createComponent()
# createNamedComponent()
# setStateMachine()
# setOrthogonal()

smacc::ISmaccUpdatable

- periodDuration_
- lastUpdate_

+ ISmaccUpdatable()
+ ISmaccUpdatable()
+ executeUpdate()
+ setUpdatePeriod()
# update()

sm_moveit_3::cl_perception _system::ClPerceptionSystem

+ detectedCubePose0
+ detectedCubePose1
+ detectedCubePose2
+ originalCube0Pose
+ originalCube1Pose
+ originalCube2Pose
+ cube0DestinationInTable1
+ cube1DestinationInTable0
+ cube2DestinationInTable1
+ startTime
+ readDelay
+ decissionsCount
+ currentCube
+ tfListener_
+ tfBroadcaster_
+ gazeboStateSubscriber_
+ lastUpdateStamp_
+ updatePeriod_
+ tableCollision_
+ cubeCollision_
+ planningInterface_

+ ClPerceptionSystem()
+ ~ClPerceptionSystem()
+ initialize()
+ simulatedLinkStateCallback()
+ propagateLinkStatesToTf()
+ nextCube()
+ retryCubeAfterFail()
+ tryCaptureInitialCubePoses()
+ update()
+ getCurrentTable()
+ decidePickCubePose()
+ decidePlacePose()