```
::onEntry
                                         cl_ros_timer::CbTimerCountdown
                                                   Once::onEntry
                                             sm_fetch_six_table
                                              pick n sort 1::cl gripper
                                             ::CbOpenGripper::onEntry
                                              sm_fetch_two_table
                                              _pick_n_place_1::cl
                                              _gripper::CbOpenGripper
                                                      ::onEntry
                                              sm fetch two table
                                              _pick_n_place_1::cl
                                              _gripper::CbCloseGripper
                                                      ::onEntry
                                             sm_fetch_six_table
                                              _pick_n_sort_1::cl_gripper
                                             ::CbCloseGripper::onEntry
                                         cl_ros_timer::CbTimerCountdown
                                                    Loop::onEntry
                                               sm dance bot::cl led
                                                 ::CbLEDOff::onEntry
                                              sm_dance_bot_strikes
_back::cl_led::CbLEDOff
                                                      ::onEntry
                                             sm_ridgeback_floor
                                               _coverage_static_1::
                                             cl_led::CbLEDOn::onEntry
                                             sm ridgeback floor
                                              _coverage_dynamic_1
                                             ::cl_led::CbLEDOff::onEntry
                                             sm_ridgeback_floor
                                               _coverage_static_1::
                                             cl_led::CbLEDOff::onEntry
                                               sm dance bot::cl led
                                                 ::CbLEDOn::onEntry
                                              sm_dance_bot_strikes
                                              _back::cl led::CbLEDOn
                                                      ::onEntry
                                             sm_ridgeback_floor
                                              _coverage_dynamic_1
                                             ::cl led::CbLEDOn::onEntry
                                          cl keyboard::CbDefaultKeyboard
                                                 Behavior::onEntry
                                             cl_move_group_interface
::CbDetachObject::onEntry
                                           cl_move_base_z::CbNavigate
                                               NextWaypoint::onEntry
                                             cl move group interface
                                             ::CbAttachObject::onEntry
                                            sm_dance_bot_strikes
smacc::ISmaccClientBehavior
                                             back::cl_string_publisher
       ::requiresClient
                                            ::CbStringPublisher::onEntry
                                            sm_ridgeback_floor
                                            _coverage_dynamic_1
::cl_string_publisher
::CbStringPublisher::onEntry
                                             sm_ridgeback_floor
                                              coverage_static_1::
                                             cl_string_publisher::
                                             CbStringPublisher::onEntry
                                            sm_dance_bot::cl_string
                                            _publisher::CbStringPublisher
                                                      ::onEntry
                                           cl move base z::CbUndoPath
                                                Backwards::onEntry
                                           cl_move_group_interface
                                           ::CbMoveEndEffector::onEntry
                                              cl_move_group_interface
                                              ::CbMoveJoints::onEntry
                                            cl_move_group_interface
                                            ::CbMoveEndEffectorRelative
                                                      ::onEntry
                                          cl move group interface
                                          ::CbMoveNamedTarget::onEntry
                                           cl_move_group_interface
::CbMoveEndEffectorTrajectory
                                                      ::onEntry
                                             cl_move_group_interface ::CbMoveCartesianRelative
                                                      ::onEntry
                                             cl_move_base_z::CbRotate
                                                      ::onEntry
                                             cl_ros_publisher::CbPublish
                                                   Once::onEntry
                                            cl_move_base_z::CbAbsolute
                                                   Rotate::onEntry
                                           cl move base z::CbNavigate
                                                Backwards::onEntry
                                           cl_move_base_z::CbNavigate
                                                  Forward::onEntry
                                           cl_move_base_z::CbNavigate
                                              GlobalPosition::onEntry
                                            cl_ros_publisher::CbDefault
                                                PublishLoop::onEntry
                                         cl multirole sensor
                                         ::CbDefaultMultiRoleSensor
                                         Behavior < sm_dance_bot_strikes
                                          back::cl lidar::ClLidarSensor
                                                     >::onEntry
                                           cl_move_base_z::CbUndoPath
```

Backwards::onExit

cl_ros_timer::CbTimer