## smacc::ISmaccClientBehavior stateMachine - currentState - currentOrthogonal + ISmaccClientBehavior() + ~ISmaccClientBehavior() + getStateMachine() + getName() + requiresClient() + requiresComponent() + getNode() # 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() + executeUpdate() + ~SmaccAsyncClientBehavior() + 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 **Event** postMotionExecutionFailure Events autocleanmarkers + CbMoveEndEffectorTrajectory() + CbMoveEndEffectorTrajectory() + onOrthogonalAllocation() + onEntry() + onExit() + update() # computeJointSpaceTrajectory() # executeJointSpaceTrajectory() # generateTrajectory() # createMarkers() # getCurrentEndEffectorPose() initializeROS() Д cl\_move\_group\_interface ::CbExecuteLastTrajectory

+ CbExecuteLastTrajectory()
+ ~CbExecuteLastTrajectory()

+ onEntry()