## smacc::ISmaccClientBehavior - stateMachine currentState - currentOrthogonal + ISmaccClientBehavior() ~ISmaccClientBehavior() + getStateMachine() + getName() + requiresClient() + requiresComponent() + getNode() # runtimeConfigure() # onEntry() # onExit() # postEvent() # postEvent() # getCurrentState() # executeOnEntry() # executeOnExit() # dispose() - onOrthogonalAllocation() smacc::SmaccAsyncClientBehavior onEntryThread\_ - onExitThread - postFinishEventFn postSuccessEventFn\_ postFailureEventFn\_ - onFinished\_ onSuccess\_ - onFailure + onOrthogonalAllocation() + ~SmaccAsyncClientBehavior() + onSuccess() + onFinished() + onFailure() # executeOnEntry() # executeOnExit() # postSuccessEvent() # postFailureEvent() # dispose() Δ smacc::ISmaccUpdatable cl\_move\_base\_z::CbMoveBase ClientBehaviorBase periodDuration\_ lastUpdate # moveBaseClient # visualizationMarkersPub + ISmaccUpdatable() + ISmaccUpdatable() + onOrthogonalAllocation() + executeUpdate() propagateSuccessEvent() + setUpdatePeriod() propagateFailureEvent() # update() cl\_move\_base\_z::CbUndoPath Backwards2 - goal - odomTracker\_ - listener - robotPose goalLinePassed initial\_plane\_side\_ triggerThreshold postVirtualLinePassed + CbUndoPathBackwards2() + onEntry() + onExit() + update() + onOrthogonalAllocation() - publishMarkers() - evalPlaneSide()