smacc::ISmaccClientBehavior stateMachine_ - currentState - currentOrthogonal + ISmaccClientBehavior() + ~ISmaccClientBehavior() + getStateMachine() + getName() + requiresClient() + requiresComponent() # 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() + ~SmaccAsyncClientBehavior() + executeUpdate() + 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 - postMotionExecutionFailure **Events** autocleanmarkers + CbMoveEndEffectorTrajectory() + CbMoveEndEffectorTrajectory() + onOrthogonalAllocation() + onEntry() + onExit() + update() # computeJointSpaceTrajectory() # execute|ointSpaceTrajectory() # generateTrajectory() # createMarkers() # getCurrentEndEffectorPose() initializeROS() cl_move_group_interface ::CbCircularPivotMotion + angularSpeed_rad_s_ + linearSpeed m s + relativelnitialPose # planePivotPose_ # deltaRadians + CbCircularPivotMotion() + CbCircularPivotMotion() + CbCircularPivotMotion() + generateTrajectorv() + createMarkers() - computeCurrentEndEffector PoseRelativeToPivot()

cl_move_group_interface ::CbEndEffectorRotate

+ CbEndEffectorRotate()
+ ~CbEndEffectorRotate()

+ onEntry()