## 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 periodDuration ClientBehaviorBase lastUpdate\_ # moveBaseClient + ISmaccUpdatable() + ISmaccUpdatable() + onOrthogonalAllocation() propagateSuccessEvent() + executeUpdate() + setUpdatePeriod() propagateFailureEvent() # update() cl\_move\_base\_z::CbUndoPath Backwards2 - goal - listener - robotPose goalLinePassed + CbUndoPathBackwards2() + onEntry() + onExit() + update()