smacc::ISmaccClientBehavior stateMachine_ currentState - currentOrthogonal + ISmaccClientBehavior() + ~ISmaccClientBehavior() + getStateMachine() + getName() + requiresClient() + requiresComponent() + getNode() # runtimeConfigure() # onEntry() # onExit() # postEvent() # postEvent() # getCurrentState() # executeOnEntry() # executeOnExit() # dispose() onOrthogonalAllocation() Д 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 **Event** postMotionExecutionFailure **Events** autocleanmarkers + CbMoveEndEffectorTrajectory() + CbMoveEndEffectorTrajectory() + onOrthogonalAllocation() + onEntry() + onExit() + update() # computeJointSpaceTrajectory() # executeJointSpaceTrajectory() # generateTrajectory() # createMarkers() # getCurrentEndEffectorPose() initializeROS() Δ cl move group interface ::CbCircularPivotMotion + angularSpeed rad s + linearSpeed_m_s + relativeInitialPose # planePivotPose_ # deltaRadians + CbCircularPivotMotion() + CbCircularPivotMotion() + CbCircularPivotMotion() + generateTrajectory() + createMarkers() computeCurrentEndEffector PoseRelativeToPivot()

cl_move_group_interface ::CbEndEffectorRotate

Д

- + CbEndEffectorRotate()
- + ~CbEndEffectorRotate() + onEntry()