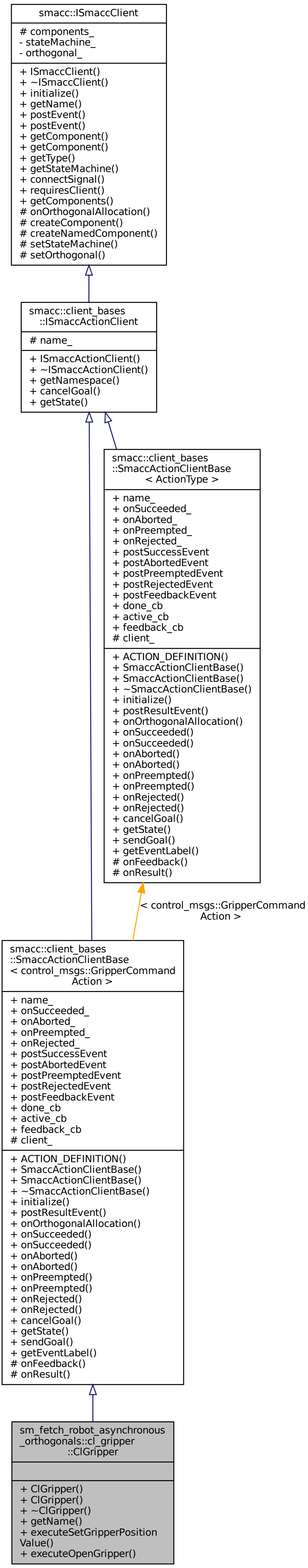
smacc::ISmaccClient
components_
- stateMachine_
- orthogonal_
+ ISmaccClient()
+ ~ISmaccClient()
+ initialize()
+ getName()
+ postEvent()
+ postEvent()
+ getComponent()
+ getComponent()
+ getType()
+ getStateMachine()
+ connectSignal()
+ requiresClient()
+ getComponents()
# onOrthogonalAllocation()
# createComponent()
# createNamedComponent()
# setStateMachine()
# setOrthogonal()
smacc::client_bases ::ISmaccActionClient
name_
+ ISmaccActionClient()
+ ~ISmaccActionClient()
+ getNamespace()
+ cancelGoal()
+ getState()
smacc::client_bases ::SmaccActionClientBase < ActionType >
+ name_
+ onSucceeded_
+ onAborted_
+ onPreempted_
+ onRejected_
+ postSuccessEvent
+ postAbortedEvent
+ postPreemptedEvent
+ postRejectedEvent
+ postFeedbackEvent
+ done_cb
+ active_cb
+ feedback_cb
# client_
+ ACTION_DEFINITION()
+ SmaccActionClientBase()
+ SmaccActionClientBase()
+ ~SmaccActionClientBase()
+ initialize()
+ postResultEvent()
+ onOrthogonalAllocation()
+ onSucceeded()
+ onSucceeded()
+ onAborted()
+ onAborted()
+ onPreempted()
+ onPreempted()
+ onRejected()
+ onRejected()
+ cancelGoal()
+ getState()
+ sendGoal()
+ getEventLabel()
# onFeedback()
# onResult()
< control_msgs::GripperCommand Action >
smacc::client_bases ::SmaccActionClientBase < control_msgs::GripperCommand Action >
+ name_
+ onSucceeded_
+ onAborted_
+ onPreempted_
+ onRejected_
+ postSuccessEvent
+ postAbortedEvent
+ postPreemptedEvent
+ postRejectedEvent
+ postFeedbackEvent
+ done_cb
+ active_cb
+ feedback_cb
# client_
+ ACTION_DEFINITION()
+ SmaccActionClientBase()
+ SmaccActionClientBase()
+ ~SmaccActionClientBase()
+ initialize()
+ postResultEvent()
+ onOrthogonalAllocation()
+ onSucceeded()
+ onSucceeded()
+ onAborted()
+ onAborted()
+ onPreempted()
+ onPreempted()
+ onRejected()
+ onRejected()
+ cancelGoal()
+ getState()
+ sendGoal()
+ getEventLabel()
# onFeedback()
# onResult()
sm_fetch_robot_asynchronous _orthogonals::cl_gripper ::ClGripper
+ ClGripper()
+ ClGripper()
+ ~ClGripper()
+ getName()
+ executeSetGripperPosition Value()
+ executeOpenGripper()