## cl move base z::Pose cl ros publisher::CbDefault + isInitialized

- deferedPublishFn
- client

- pose

- tfListener

- m mutex

+ Pose()

+ update()

+ toPoseMsq()

- poseFrameName

+ waitTransformUpdate()

+ toPoseStampedMsq()

+ getReferenceFrame()

- referenceFrame

- + CbDefaultPublishLoop()
- + CbDefaultPublishLoop()
- + setMessage()
- + onEntry()
- + update()
- + onExit()

- PublishLoop

sm moveit::cl perception system::CIPerceptionSystem

smacc::ISmaccUpdatable

- periodDuration - lastUpdate

# update()

+ ISmaccUpdatable() + ISmaccUpdatable() + executeUpdate() + setUpdatePeriod()

- + detectedCubePose0
- + detectedCubePose1
- + detectedCubePose2
- + originalCube0Pose
- + originalCube1Pose
- + originalCube2Pose
- + cube0DestinationInTable1
- + cube1DestinationInTable0
- + cube2DestinationInTable1
- + startTime
- + readDelay
- + decissionsCount
- + currentCube
- + CIPerceptionSystem()
- + ~CIPerceptionSystem()
- + nextCube()
- + retryCubeAfterFail()
- + update()
- + getCurrentTable()
- + decidePickCubePose()
- + decidePlacePose()

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- smacc::state reactors ::SrRandomGenerator
- + mode
- postEventA
- postEventB
- postEventC
- evAMin
- evAMax
- evBMin -
- evBMax
- evCMin
- evCMax
- minValue
- maxValue
- + SrRandomGenerator()
- + onEntry()
- + declareObjectTag()
- + postRandomEvents()
- + update()
- + onEventNotified()