## smacc::ISmaccClientBehavior stateMachine\_ - currentState - currentOrthogonal + ISmaccClientBehavior() + ~ISmaccClientBehavior() + getStateMachine() + getName() + requiresClient() + requiresComponent() # 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 postMotionExecutionFailure **Events** - autocleanmarkers + CbMoveEndEffectorTrajectory() + CbMoveEndEffectorTrajectory() + onOrthogonalAllocation() + onEntry() + onExit() + update() # computeJointSpaceTrajectory() # executeJointSpaceTrajectory() # generateTrajectory() # createMarkers() initializeROS() 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

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+ CbEndEffectorRotate() + ~CbEndEffectorRotate()

+ onEntry()