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() # getCurrentEndEffectorPose() - initializeROS() cl_move_group_interface ::CbCircularPouringMotion + angularSpeed_rad_s_ + linearSpeed_m_s_ + directionVector + pointerRelativePose # relativePivotPoint_ # deltaHeight_ # pointerTrajectory_ globalFrame_

+ CbCircularPouringMotion()+ generateTrajectory()+ createMarkers()

computeCurrentEndEffector

PoseRelativeToPivot()