## 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 ::CbCircularPouringMotion + angularSpeed\_rad\_s\_ + linearSpeed\_m\_s\_ + directionVector + pointerRelativePose # pivotPoint # deltaHeight # pointerTrajectory\_

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

+ getCurrentEndEffectorPose()- computeCurrentEndEffector

PoseRelativeToPivot()