**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()

---

< sm_dance_bot_strikes_back::LEDControlAction >

< control_msgs::GripperCommandAction >

< move_base_msgs::MoveBaseAction >

< sm_dance_bot_2::LEDControlAction >

< sm_dance_bot::LEDControlAction >

---

**smacc::client_bases::SmaccActionClientBase< sm_dance_bot_strikes_back::LEDControlAction >**

+ 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()

---

**smacc::client_bases::SmaccActionClientBase< control_msgs::GripperCommandAction >**

+ 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()

---

**smacc::client_bases::SmaccActionClientBase< move_base_msgs::MoveBaseAction >**

+ 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()

---

**smacc::client_bases::SmaccActionClientBase< sm_dance_bot_2::LEDControlAction >**

+ 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()

---

**smacc::client_bases::SmaccActionClientBase< sm_dance_bot::LEDControlAction >**

+ 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_dance_bot_strikes_back::cl_led::ClLED**

+ SMACC_ACTION_CLIENT_DEFINITION()
+ ClLED()
+ getName()
+ ~ClLED()

---

**sm_fetch_screw_loop_1::cl_gripper::ClGripper**

+ ClGripper()
+ ClGripper()
+ ~ClGripper()
+ getName()
+ executeSetGripperPositionValue()
+ executeOpenGripper()

---

**sm_fetch_six_table_pick_n_sort_1::cl_gripper::ClGripper**

+ ClGripper()
+ ClGripper()
+ ~ClGripper()
+ getName()
+ executeSetGripperPositionValue()
+ executeOpenGripper()

---

**sm_fetch_two_table_pick_n_place_1::cl_gripper::ClGripper**

+ ClGripper()
+ ClGripper()
+ ~ClGripper()
+ getName()
+ executeSetGripperPositionValue()
+ executeOpenGripper()

---

**sm_fetch_two_table_whiskey_pour::cl_gripper::ClGripper**

+ ClGripper()
+ ClGripper()
+ ~ClGripper()
+ getName()
+ executeSetGripperPositionValue()
+ executeOpenGripper()

---

**cl_move_base_z::ClMoveBaseZ**

+ ClMoveBaseZ()
+ ClMoveBaseZ()
+ initialize()
+ getName()

---

**sm_dance_bot_2::cl_led::ClLED**

+ SMACC_ACTION_CLIENT_DEFINITION()
+ ClLED()
+ getName()
+ ~ClLED()

---

**sm_dance_bot::cl_led::ClLED**

+ SMACC_ACTION_CLIENT_DEFINITION()
+ ClLED()
+ getName()
+ ~ClLED()