## stateMachine - currentState - currentOrthogonal + ISmaccClientBehavior() + ~ISmaccClientBehavior() + getStateMachine() + getName() + requiresClient() + requiresComponent() + onEntry() + onExit() + executeOnEntry() + executeOnExit() # runtimeConfigure() # postEvent() # postEvent() # getCurrentState() # dispose() #getNode() # getLogger() - onOrthogonalAllocation() Δ smacc2::SmaccAsyncClient Behavior - onEntryThread\_ - onExitThread postFinishEventFn postSuccessEventFn\_ postFailureEventFn onFinished - onSuccess\_ onFailure isShutdownRequested\_ + onOrthogonalAllocation() + ~SmaccAsyncClientBehavior() + onSuccess() + onFinished() + onFailure() + requestForceFinish() + executeOnEntry() + executeOnExit() + waitOnEntryThread() + onSuccess() + onFinished() + onFailure() # postSuccessEvent() # postFailureEvent() #dispose() #isShutdownRequested() - waitFutureIfNotFinished() cl\_nav2z::CbNav2ZClientBehaviorBase # nav2zClient # navigationCallback\_ # navigationResult # goalHandleFuture + ~CbNav2ZClientBehaviorBase() + onOrthogonalAllocation() # sendGoal() # cancelGoal() #isOwnActionResponse() # onNavigationResult() # onNavigationActionSuccess() # onNavigationActionAbort() cl\_nav2z::CbNavigateNext Waypoint # waypointsNavigator\_ # options # navigationCallback\_ + CbNavigateNextWaypoint() + ~CbNavigateNextWaypoint() + onEntry() + onExit() cl\_nav2z::CbNavigateNext WaypointUntilReached cl nav2z::CbNavigateNamed - goalWaypointName Waypoint - postEvGoalWaypointReached\_ + waypointsNavigator\_ + CbNavigateNextWaypointUntil + waypointname Reached() + CbNavigateNamedWaypoint() + ~CbNavigateNextWaypointUntil Reached() + ~CbNavigateNamedWaypoint() + onOrthogonalAllocation() + onEntry() + onExit() + onNavigationActionSuccess()

+ onEntry() + onExit()

smacc2::ISmaccClientBehavior