stateMachine currentState currentOrthogonal + ISmaccClientBehavior() + ~ISmaccClientBehavior() + getStateMachine() + getName() + requiresClient() + requiresComponent() + onEntry() + onExit() + executeOnEntry() + executeOnExit() # runtimeConfigure() # postEvent() # postEvent() # getCurrentState() # dispose() # getNode() # getLogger() - onOrthogonalAllocation() Д smacc2::SmaccAsyncClient Behavior $\hbox{-} on Entry Thread \\$ 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 # navigationResult_ # goalHandleFuture_ + ~CbNav2ZClientBehaviorBase() + onOrthogonalAllocation() # sendGoal() # isOwnActionResponse() # onNavigationActionSuccess() # onNavigationActionAbort() Д cl_nav2z::CbNavigateNext Waypoint # waypointsNavigator_ # options + CbNavigateNextWaypoint() + ~CbNavigateNextWaypoint() + onEntry() + onExit() cl nav2z::CbNavigateNext WaypointUntilReached cl_nav2z::CbNavigateNamed goalWaypointName Waypoint - postEvGoalWaypointReached + waypointsNavigator_ + CbNavigateNextWaypointUntil + waypointname_ Reached() + CbNavigateNamedWaypoint() + ~CbNavigateNextWaypointUntil + ~CbNavigateNamedWaypoint() Reached() + onOrthogonalAllocation() + onEntry() + onExit() + onNavigationActionSuccess()

+ onEntry()

+ onExit()

smacc2::ISmaccClientBehavior