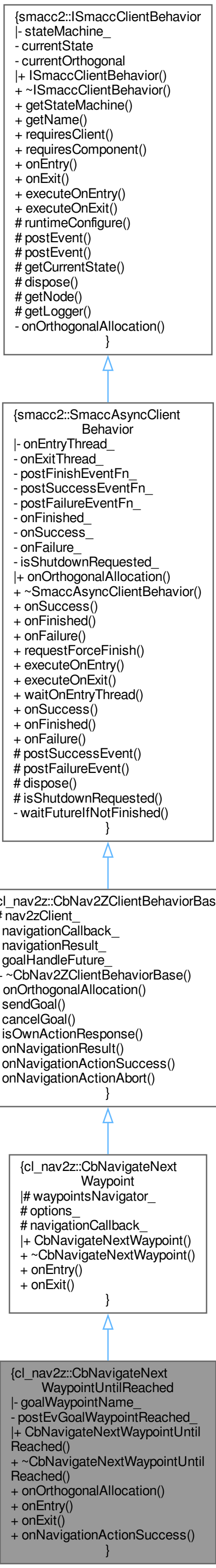
{smacc2::ISmaccClientBehavior
|- stateMachine_
- currentState
- currentOrthogonal
|+ ISmaccClientBehavior()
+ ~ISmaccClientBehavior()
+ getStateMachine()
+ getName()
+ requiresClient()
+ requiresComponent()
+ onEntry()
+ onExit()
+ executeOnEntry()
+ executeOnExit()
# runtimeConfigure()
# postEvent()
# postEvent()
# getCurrentState()
# dispose()
# getNode()
# getLogger()
- onOrthogonalAllocation()
}
{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
|- goalWaypointName_
- postEvGoalWaypointReached_
|+ CbNavigateNextWaypointUntil Reached()
+ ~CbNavigateNextWaypointUntil Reached()
+ onOrthogonalAllocation()
+ onEntry()
+ onExit()
+ onNavigationActionSuccess()
}