smacc::ISmaccClientBehavior - stateMachine currentState - currentOrthogonal + ISmaccClientBehavior() + ~ISmaccClientBehavior() + getStateMachine() + getName() + requiresClient() + requiresComponent() + getNode() # runtimeConfigure() # onEntry() # onExit() # postEvent() # postEvent() # getCurrentState() # executeOnEntry() # executeOnExit() # dispose() - on Orthogonal Allocation() smacc::SmaccAsyncClientBehavior - on Entry Thread - onExitThread - postFinishEventFn postSuccessEventFn_ - postFailureEventFn_ - onFinished - onSuccess - onFailure + onOrthogonalAllocation() + ~SmaccAsyncClientBehavior() + onSuccess() + onFinished() + onFailure() # executeOnEntry() # executeOnExit() # postSuccessEvent() # postFailureEvent() #dispose() smacc::ISmaccUpdatable cl_move_base_z::CbMoveBase ClientBehaviorBase periodDuration_ lastUpdate # moveBaseClient # visualizationMarkersPub + ISmaccUpdatable() + ISmaccUpdatable() + onOrthogonalAllocation() + executeUpdate() propagateSuccessEvent() + setUpdatePeriod() - propagateFailureEvent() # update() cl_move_base_z::CbUndoPath Backwards2 -goal odomTracker - listener - robotPose - goalLinePassed - initial_plane_side - triggerThreshold - postVirtualLinePassed + CbUndoPathBackwards2() + onEntry() + onExit() + update() + onOrthogonalAllocation() - publishMarkers() - evalPlaneSide()