## smacc::ISmaccClientBehavior stateMachine currentState currentOrthogonal + ISmaccClientBehavior() + ~ISmaccClientBehavior() + getStateMachine() + getName() + requiresClient() + requiresComponent() + getNode() # runtimeConfigure() # onEntry() # onExit() # postEvent() # postEvent() # getCurrentState() # executeOnEntry() # executeOnExit() # dispose() - onOrthogonalAllocation() Δ smacc::SmaccAsyncClientBehavior onEntryThread\_ onExitThread\_ postFinishEventFn postSuccessEventFn smacc::ISmaccUpdatable postFailureEventFn\_ onFinished periodDuration\_ - onSuccess lastUpdate - onFailure + ISmaccUpdatable() + onOrthogonalAllocation() + ISmaccUpdatable() + ~SmaccAsyncClientBehavior() + executeUpdate() + onSuccess() + setUpdatePeriod() + onFinished() # update() + onFailure() # executeOnEntry() # executeOnExit() # postSuccessEvent() # postFailureEvent() # dispose() cl\_move\_group\_interface ::CbMoveEndEffectorTrajectory + group + tipLink + allowInitialTrajectoryState JointDiscontinuity # endEffectorTrajectory\_ # movegroupClient # beahiorMarkers\_ markersPub markersInitialized iksrv - m\_mutex\_ postJointDiscontinuityEvent - postIncorrectInitialState **Event** - postMotionExecutionFailure **Events** - autocleanmarkers + CbMoveEndEffectorTrajectory() + CbMoveEndEffectorTrajectory() + onOrthogonalAllocation() + onEntry() + onExit() + update() # computeJointSpaceTrajectory() # executeJointSpaceTrajectory() # generateTrajectory() # createMarkers() # getCurrentEndEffectorPose() - initializeROS() cl\_move\_group\_interface ::CbCircularPouringMotion + angularSpeed\_rad\_s\_ + linearSpeed\_m\_s\_ + directionVector + pointerRelativePose # relativePivotPoint\_ # deltaHeight\_ # pointerTrajectory\_

globalFrame\_

+ CbCircularPouringMotion() + generateTrajectory() + createMarkers()

- computeCurrentEndEffector PoseRelativeToPivot()