## smacc::ISmaccComponent

## # stateMachine

- + ISmaccComponent()
- + ~ISmaccComponent()
- + initialize()
- + setStateMachine()
- + getName()
- + postEvent()

## ::OdomTracker

# robotBasePathPub\_

smacc odom tracker

- # odomSub
- # minPointDistanceForwardThresh
- # minPointDistanceBackward
- Thresh
- # minPointAngularDistanceForward
- Thresh
- # minPointAngularDistanceBackward
- Thresh\_
- # publishMessages
- # baseTrajectory\_
- # workingMode\_ # pathStack
- # subscribeToOdometryTopic
- # m mutex
- + OdomTracker()
- + initialize()
- + processOdometryMessage()
- + setWorkingMode()
- + setPublishMessages()
- + pushPath()
- + popPath()
- + clearPath()
- + setStartPoint()
- + getPath()
- # rtPublishPaths()
- # updateForward()
- # updateBackward()

## smacc::WaypointNavigator

- + waypointsEventDispatcher
- + client
- waypoints
- succeddedConnection
- currentWaypoint\_
- + WaypointNavigator()
- + assignToOrthogonal()
- + insertWaypoint()
- + removeWaypoint()
- + loadWayPointsFromFile()
- + setWaypoints()
- + setWaypoints()
- + sendNextGoal()
- + getWaypoints()
- + getCurrentWaypointIndex()
- onGoalReached()