smacc::ISmaccComponent # stateMachine # owner + ISmaccComponent() + ~ISmaccComponent() + initialize() + setStateMachine() + getName() + postEvent() + postEvent() + configureEventSourceTypes() move base z client ::WaypointNavigator + wavpointsEventDispatcher + client

sm dance bot 2::cl

+ lastMessage

+ initialize()

ToWall()

lidar::CpLidarSensorData

+ MessageCallbackStoreDistance

+ forwardObstacleDistance

Thresh_# minPointAngularDistanceForward
Thresh

minPointDistanceBackward

minPointDistanceForwardThresh

minPointAngularDistanceBackward Thresh

::odom_tracker::OdomTracker

publishMessages

move base z client

robotBasePathPub

odomSub

- # baseTrajectory_
- # workingMode_
- # pathStack_
- # subscribeToOdometryTopic_
- # m_mutex_
- + OdomTracker()
- + processOdometryMessage()
- + setWorkingMode()
- + setPublishMessages()
- + pushPath()
- + popPath()
- + clearPath()
- + setStartPoint()
- + getPath()
- # rtPublishPaths()
- # updateForward()
- # updateBackward()

- waypoints
- succeddedConnection
- currentWaypoint_
- + WaypointNavigator()
- + initialize()
- + insertWaypoint()
- + removeWaypoint()
- + loadWayPointsFromFile()
- + setWaypoints()
- + setWaypoints()
- + sendNextGoal()
- + getWaypoints()
- + getCurrentWaypointIndex()
- + configureEventSourceTypes()
- onGoalReached()