## smacc::ISmaccComponent

# stateMachine_
# owner_

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+ ISmaccComponent()
+ ~ISmaccComponent()
+ initialize()
+ setStateMachine()
+ getName()
+ postEvent()
+ postEvent()
# configureEventSourceTypes()

## move_base_z_client ::odom_tracker::OdomTracker

# robotBasePathPub_
# odomSub_
# minPointDistanceForwardThresh_
# minPointDistanceBackward Thresh_
# minPointAngularDistanceForward Thresh_
# minPointAngularDistanceBackward Thresh_
# publishMessages
# baseTrajectory_
# workingMode_
# pathStack_
# subscribeToOdometryTopic_
# m_mutex_

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+ OdomTracker()
+ processOdometryMessage()
+ setWorkingMode()
+ setPublishMessages()
+ pushPath()
+ popPath()
+ clearPath()
+ setStartPoint()
+ getPath()
# rtPublishPaths()
# updateForward()
# updateBackward()

## move_base_z_client ::WaypointNavigator

+ waypointsEventDispatcher
+ client_
- waypoints_
- succeddedConnection_
- currentWaypoint_

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