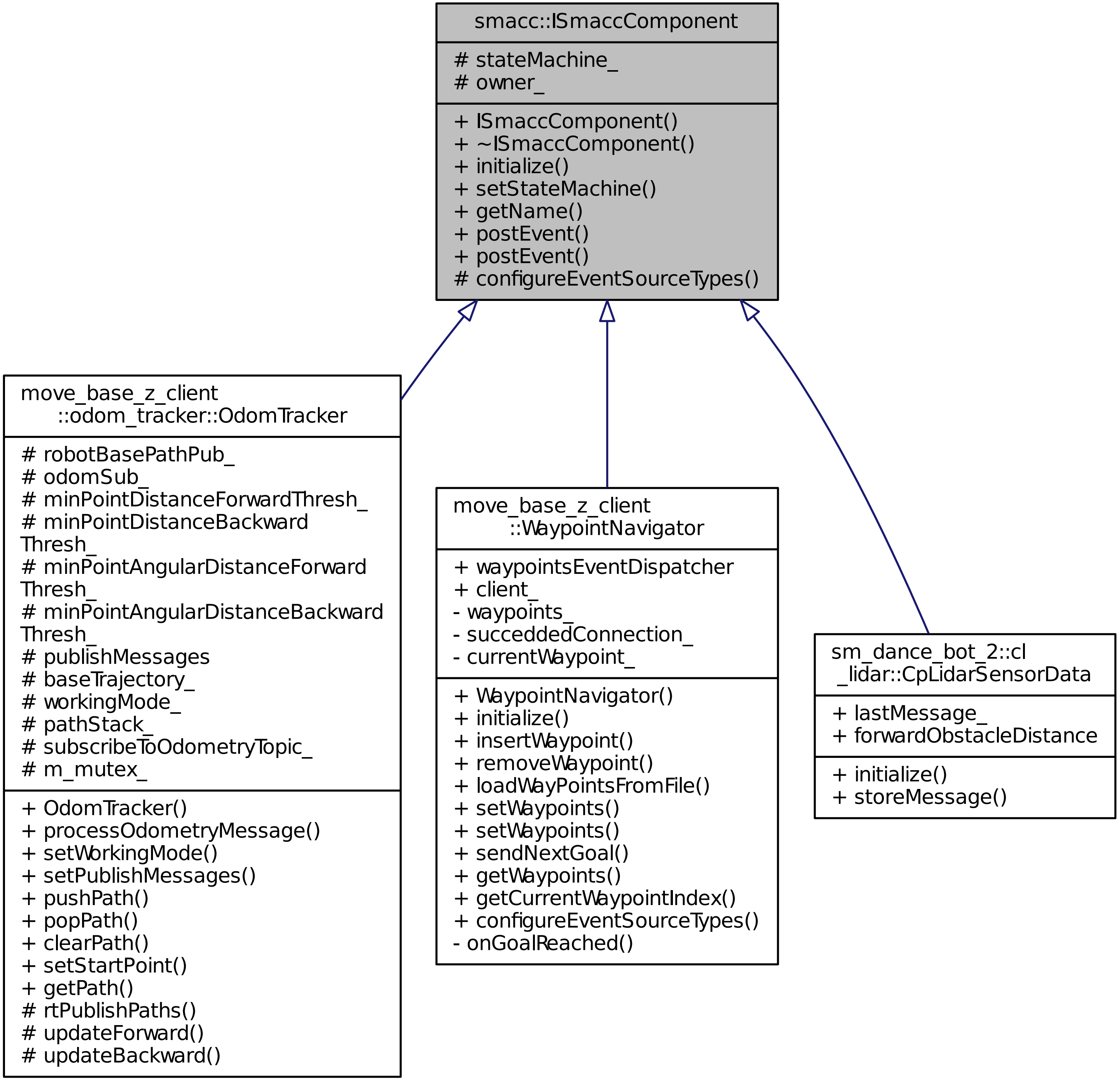

smacc::ISmaccComponent
# stateMachine_
# owner_
+ ISmaccComponent()
+ ~ISmaccComponent()
+ initialize()
+ setStateMachine()
+ getName()
+ postEvent()
+ postEvent()
# configureEventSourceTypes()
move_base_z_client
::odom_tracker::OdomTracker
# robotBasePathPub_
# odomSub_
# minPointDistanceForwardThresh_
# minPointDistanceBackward
Thresh_
# minPointAngularDistanceForward
Thresh_
# minPointAngularDistanceBackward
Thresh_
# publishMessages
# baseTrajectory_
# workingMode_
# pathStack_
# subscribeToOdometryTopic_
# m_mutex_
+ OdomTracker()
+ processOdometryMessage()
+ setWorkingMode()
+ setPublishMessages()
+ pushPath()
+ popPath()
+ clearPath()
+ setStartPoint()
+ getPath()
# rtPublishPaths()
# updateForward()
# updateBackward()
move_base_z_client
::WaypointNavigator
+ waypointsEventDispatcher
+ client_
- waypoints_
- succeddedConnection_
- currentWaypoint_
+ WaypointNavigator()
+ initialize()
+ insertWaypoint()
+ removeWaypoint()
+ loadWayPointsFromFile()
+ setWaypoints()
+ setWaypoints()
+ sendNextGoal()
+ getWaypoints()
+ getCurrentWaypointIndex()
+ configureEventSourceTypes()
- onGoalReached()
sm_dance_bot_2::cl
_lidar::CpLidarSensorData
+ lastMessage_
+ forwardObstacleDistance
+ initialize()
+ storeMessage()