smacc::ISmaccComponent

- # stateMachine_ # owner
- + ISmaccComponent()
- + ~ISmaccComponent()
- + initialize()
- + setStateMachine()
- + getName()
- + postEvent()
- + postEvent()
- # configureEventSourceTypes()

odom tracker::OdomTracker

- # robotBasePathPub
- # odomSub
- # minPointDistanceForwardThresh
- # minPointDistanceBackward Thresh
- # minPointAngularDistanceForward
- # 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()
- + initialize()
- + insertWaypoint()
- + removeWaypoint()
- + loadWayPointsFromFile()
- + setWaypoints()
- + setWaypoints()
- + sendNextGoal()
- + getWaypoints()
- + getCurrentWaypointIndex()
- + configureEventSourceTypes()
- onGoalReached()