smacc::ISmaccComponent

stateMachine_
owner_

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

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()