smacc::ISmaccComponent # stateMachine # owner + ISmaccComponent() + ~ISmaccComponent() + initialize() + setStateMachine() + getName() + postEvent() + postEvent() + configureEventSourceTypes() move base z client ::WaypointNavigator + wavpointsEventDispatcher + client - waypoints - succeddedConnection sm dance bot 2::cl currentWaypoint lidar::CpLidarSensorData + WaypointNavigator() + lastMessage + initialize() + forwardObstacleDistance + insertWaypoint() + initialize()

+ storeMessage()

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()

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