```
# components
  stateMachine_

    orthogonal

  + ISmaccClient()
  + ~ISmaccClient()
  + onInitialize()
  + getName()
  + getComponent()
  + getComponent()
  + getType()
  + getStateMachine()
  + connectSignal()
  + requiresClient()
  + getComponents()
  + postEvent()
  + postEvent()
  # onOrthogonalAllocation()
  # createComponent()
  # createNamedComponent()
  #getNode()
  # getLogger()
  initialize()
  setStateMachine()
  setOrthogonal()
  smacc::client_bases
  ::SmaccSubscriberClient
       < MessageType >
  + topicName
  + queueSize
  + onFirstMessageReceived_
  + onMessageReceived_
  + postMessageEvent
  + postInitialMessageEvent
  - sub

    firstMessage

    initialized

  + SmaccSubscriberClient()
  + SmaccSubscriberClient()
  + ~SmaccSubscriberClient()
  + onMessageReceived()
  + onFirstMessageReceived()
  + onOrthogonalAllocation()
  # onInitialize()
  messageCallback()
                     cl multirole_sensor
                     ::CIMultiroleSensor
                           < MessageType >
                     + onMessageTimeout_
                     + postTimeoutMessageEvent
                     + timeout
                      - timeoutTimer_
                     - initialized
                     + ClMultiroleSensor()
                     + onMessageTimeout()
                     + onOrthogonalAllocation()
                     + onInitialize()
                     # resetTimer()
                      timeoutCallback()
                            < sensor_msgs::msg
                              ::LaserScan >
cl_multirole_sensor
::CIMultiroleSensor
< sensor_msgs::msg::LaserScan >
+ onMessageTimeout
+ postTimeoutMessageEvent
+ timeout
timeoutTimer_

    initialized

+ CIMultiroleSensor()
+ onMessageTimeout()
+ onOrthogonalAllocation()
+ onInitialize()
# resetTimer()
timeoutCallback()
  sm dance bot strikes
   back::cl_lidar::ClLidarSensor
```

+ CILidarSensor()

smacc::ISmaccClient