```
# components_

    stateMachine

     orthogonal_
     + ISmaccClient()
     + ~ISmaccClient()
     + initialize()
     + getName()
     + postEvent()
     + postEvent()
     + getComponent()
     + configureEventSourceTypes()
     + getType()
     + getStateMachine()
     + connectSignal()
     + requiresClient()
     # createComponent()
     # setStateMachine()
     # setOrthogonal()
                    smacc::client_bases
                    :: Smacc Subs \bar{c}riber Client
                           < MessageType >
                    + topicName
                    + queueSize
                    + onFirstMessageReceived_
                    + onMessageReceived_
                    + postMessageEvent
                    + postInitialMessageEvent
                    # nh_
                    - sub

    firstMessage_

                    - initialized
                    + SmaccSubscriberClient()
                    + SmaccSubscriberClient()
                    + ~SmaccSubscriberClient()
                    + onMessageReceived()
                    + onFirstMessageReceived()
                    + configureEventSourceTypes()
                    + initialize()
                    - messageCallback()
                    < sensor_msgs::LaserScan >
smacc::client_bases
::SmaccSubscriberClient
< sensor_msgs::LaserScan >
                                     multirole_sensor_client
+ topicName
                                     ::ClMultiroleSensor< Message
+ queueSize
                                                 Type >
+ onFirstMessageReceived_
+ onMessageReceived
                                     + onMessageTimeout_
+ postMessageEvent
                                     + postTimeoutMessageEvent
+ postInitialMessageEvent
                                     + timeout
# nh

    timeoutTimer_

- sub
                                     - initialized
firstMessage_
- initialized
                                     + ClMultiroleSensor()
                                     + onMessageTimeout()
+ SmaccSubscriberClient()
                                     + configureEventSourceTypes()
+ SmaccSubscriberClient()
                                     + initialize()
+ ~SmaccSubscriberClient()
                                     # resetTimer()
+ onMessageReceived()
                                     timeoutCallback()
+ onFirstMessageReceived()
+ configureEventSourceTypes()
+ initialize()
messageCallback()
                                       < sensor_msgs::LaserScan >
           multirole_sensor_client
           ::ClMultiroleSensor< sensor
                _msgs::LaserScan >
           + onMessageTimeout
           + postTimeoutMessageEvent
           + timeout
           - timeoutTimer

    initialized

           + ClMultiroleSensor()
           + onMessageTimeout()
           + configureEventSourceTypes()
           + initialize()
           # resetTimer()
           timeoutCallback()
            sm dance bot strikes
            back::cl lidar::ClLidarSensor
```

+ ClLidarSensor()

smacc::ISmaccClient