```
smacc::SmaccClientBehavior
     - stateMachine_

    currentState

     - currentOrthogonal
     + SmaccClientBehavior()
     + ~SmaccClientBehavior()
     + getStateMachine()
     + getName()
     + runtimeConfigure()
     + onEntry()
     + onExit()
     + postEvent()
     + postEvent()
     + requiresClient()
     + requiresComponent()
     + getCurrentState()
     configureEventSourceTypes()
                    cl multirole sensor
                    ::CbDefaultMultiRoleSensor
                        Behavior < ClientType >
                    + sensor
                    + deferedEventPropagation
                    + CbDefaultMultiRoleSensor
                    Behavior()
                    + configureEventSourceTypes()
                    + propagateEvent()
                    + propagateEvent2()
                    + onEntry()
                    + onExit()
                    + onMessageCallback()
                    + getEventLabel()
                           < sm_dance_bot_strikes
                           back::cl lidar::ClLidarSensor >
cl multirole sensor
:: CbDefault MultiRole Sensor
Behavior< sm dance bot strikes
 back::cl lidar::ClLidarSensor >
+ sensor
+ deferedEventPropagation
+ CbDefaultMultiRoleSensor
Behavior()
+ configureEventSourceTypes()
+ propagateEvent()
+ propagateEvent2()
+ onEntry()
+ onExit()
+ onMessageCallback()
+ getEventLabel()
 sm dance bot strikes
  _back::cl_lidar::CbLidarSensor
 + CbLidarSensor()
 + onEntry()
 + onMessageCallback()
```