```
smacc::ISmaccClient
   # components

    stateMachine

   + ISmaccClient()
      ~lSmaccClient()
   + initialize()
   + setStateMachine()
   + getName()
   + postEvent()
    + postEvent()
   + getComponent()
   + configureEventSourceTypes()
   + getType()
   + getStateMachine()
   + connectSignal()
   # createComponent()
                   smacc::client_bases
                   ::SmaccSubscriberClient
                         < MessageType >
                   + topicName
                   + queueSize
                   + onFirstMessageReceived_
                   + onMessageReceived_
                   + postMessageEvent
                   + postInitialMessageEvent
# nh_
                   - sub
                   - firstMessage_
                   - initialized
                   + SmaccSubscriberClient()
                   + SmaccSubscriberClient()
                   + ~SmaccSubscriberClient()
                   + onMessageReceived()
                   + onFirstMessageReceived()
                   + configureEventSourceTypes()
                   + initialize()
                   messageCallback()
                         < ClLidarSensor >
smacc::client bases
::SmaccSubscriberClient
      < ClLidarSensor >
+ topicName
+ queueSize
+ onFirstMessageReceived
+ onMessageReceived
+ postMessageEvent
+ postInitialMessageEvent
# nh
- sub
- firstMessage
- initialized
  SmaccSubscriberClient()
+ SmaccSubscriberClient()
+ ~SmaccSubscriberClient()
+ onMessageReceived()
+ onFirstMessageReceived()
+ configureEventSourceTypes()
+ initialize()
```

sm\_dance\_bot\_2::cl \_lidar::CbLidarSensor

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messageCallback()

- + CbLidarSensor()
- + onEntry()
- + onMessageCallback()