```
smacc::ISmaccComponent
  # stateMachine
  # serviceName
  # owner
  + ISmaccComponent()
  + ~ISmaccComponent()
  + initialize()
  + setStateMachine()
  + getName()
  + postEvent()
  + postEvent()
  + configureEventSourceTypes()
cl move base z::odom
       tracker::OdomTracker
# robotBasePathPub
# robotBasePathStackedPub
# odomSub
# recordPointDistanceThreshold
# recordAngularDistanceThreshold
# clearPointDistanceThreshold
# clearAngularDistanceThreshold
# odomFrame
# publishMessages
# baseTrajectory
# workingMode
# pathStack
# aggregatedStackPathMsg
# subscribeToOdometryTopic
# m mutex
+ OdomTracker()
+ processOdometryMessage()
+ setWorkingMode()
+ setPublishMessages()
+ pushPath()
+ popPath()
+ clearPath()
+ setStartPoint()
+ setStartPoint()
+ getPath()
+ logStateString()
# rtPublishPaths()
# updateRecordPath()
# updateClearPath()
# updateAggregatedStackPath()
```