smacc::ISmaccComponent

stateMachine_
owner_

+ ISmaccComponent()
+ ~ISmaccComponent()
+ initialize()
+ setStateMachine()
+ getName()
+ postEvent()
+ postEvent()
+ configureEventSourceTypes()

move_base_z_client ::odom_tracker::OdomTracker

robotBasePathPub_
odomSub_
minPointDistanceForwardThresh_
minPointDistanceBackward
Thresh_
minPointAngularDistanceForward
Thresh_
minPointAngularDistanceBackward
Thresh_
publishMessages
baseTrajectory_
workingMode_
pathStack_
subscribeToOdometryTopic_
m_mutex_

+ OdomTracker()
+ processOdometryMessage()
+ setWorkingMode()
+ setPublishMessages()
+ pushPath()
+ popPath()
+ clearPath()
+ setStartPoint()
+ getPath()
# rtPublishPaths()
# updateForward()
# updateBackward()

move_base_z_client ::PlannerSwitcher

- desired_global_planner_
- desired_local_planner_
- dynrecofSub_
- set_planners_mode_flag

+ PlannerSwitcher()
+ setBackwardPlanner()
+ setForwardPlanner()
+ setDefaultPlanners()
- updatePlanners()
- dynreconfCallback()

move_base_z_client ::WaypointNavigator

+ waypointsEventDispatcher
+ client_
+ currentWaypoint_
- waypoints_
- succeddedConnection_

+ WaypointNavigator()
+ initialize()
+ insertWaypoint()
+ removeWaypoint()
+ loadWayPointsFromFile()
+ setWaypoints()
+ setWaypoints()
+ sendNextGoal()
+ getWaypoints()
+ getCurrentWaypointIndex()
+ configureEventSourceTypes()
- onGoalReached()

sm_dance_bot_2::cl _lidar::CpLidarSensorData

+ lastMessage_
+ forwardObstacleDistance
+ SECURITY_DISTANCE

+ initialize()
+ MessageCallbackStoreDistance
ToWall()