```
smacc::ISmaccClient
   # components
    stateMachine
   + ISmaccClient()
   + ~ISmaccClient()
   + initialize()
   + setStateMachine()
   + getName()
   + postEvent()
   + postEvent()
   + getComponent()
   + configureEventSourceTypes()
   + getType()
   + getStateMachine()
   # 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()
```

sm_dance_bot_2::cl _lidar::CbLidarSensor

Δ

+ onFirstMessageReceived() + configureEventSourceTypes()

+ initialize()

messageCallback()

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