

smacc2::ISmaccComponent
# stateMachine_ # owner_
+ ISmaccComponent() + ~ISmaccComponent() + getName() # onInitialize() # postEvent() # postEvent() # onOrthogonalAllocation() # requiresComponent() # requiresComponent() # requiresClient() # createSiblingComponent() # createSiblingNamedComponent() # getNode() # getLogger() # getStateMachine() - initialize() - setStateMachine()



cl_nav2z::odom_tracker ::CpOdomTracker
# robotBasePathPub_ # robotBasePathStackedPub_ # odomSub_ # recordPointDistanceThreshold_ # recordAngularDistanceThreshold_ # clearPointDistanceThreshold_ # clearAngularDistanceThreshold_ # odomFrame_ # odomTopicName_ # publishMessages # baseTrajectory_ # workingMode_ # pathStack_ # pathInfos_ # aggregatedStackPathMsg_ # subscribeToOdometryTopic_ # currentMotionGoal_ # currentPathName_ # m_mutex_
+ CpOdomTracker() + processOdometryMessage() + setWorkingMode() + setPublishMessages() + pushPath() + pushPath() + popPath() + clearPath() + setStartPoint() + setStartPoint() + setCurrentMotionGoal() + setCurrentPathName() + getCurrentMotionGoal() + getPath() + logStateString() # onInitialize() # updateConfiguration() # rtPublishPaths() # updateRecordPath() # updateClearPath() # updateAggregatedStackPath()