```
smacc2::ISmaccClientBehavior
      stateMachine
      currentState
     currentOrthogonal
     ISmaccClientBehavior()
  +
     ~ISmaccClientBehavior()
  +
     getStateMachine()
  +
     getName()
  +
     requiresClient()
  +
     requiresComponent()
  +
     onEntry()
    onExit()
  +
     executeOnEntry()
     executeOnExit()
     runtimeConfigure()
  # postEvent()
      postEvent()
  #
     getCurrentState()
  #
     dispose()
  #
     getNode()
  #
    getLogger()
      onOrthogonalAllocation()
   smacc2::SmaccAsyncClient
             Behavior

    onEntryThread_

    onExitThread

    postFinishEventFn

    postSuccessEventFn

    postFailureEventFn

    onFinished

 - onSuccess_
 - onFailure_
  isShutdownRequested_
 + onOrthogonalAllocation()
 + ~SmaccAsyncClientBehavior()
 + onSuccess()
 + onFinished()
 + onFailure()
 + requestForceFinish()
 + executeOnEntry()
 + executeOnExit()
 + waitOnEntryThread()
 + onSuccess()
 + onFinished()
 + onFailure()
 # postSuccessEvent()
 # postFailureEvent()
 # dispose()
 # isShutdownRequested()
 - waitFutureIfNotFinished()
   cl nav2z::CbPositionControl
           FreeSpace
 + yaw_goal_tolerance
    rads
 + threshold distance
 + target_pose_
 targetYaw_

    goalReached_

    k_betta_

  max_angular_yaw_speed_

    prev_error_linear_

    prev_error_angular_

    integral_linear_

    integral_angular

    max_linear_velocity

    max_angular_velocity

 cmd_vel_pub_
 + CbPositionControlFreeSpace()
 + updateParameters()
 + onEntry()
 + onExit()
    cl_nav2z::CbNavigateNext
          WaypointFree
# waypointsNavigator_
+ CbNavigateNextWaypointFree()
+ ~CbNavigateNextWaypointFree()
```

+ onEntry()

+ onExit()

+ onSucessCallback()