```
smacc2::ISmaccClientBehavior

    stateMachine

    - currentState
   - currentOrthogonal
   + ISmaccClientBehavior()
   + ~ISmaccClientBehavior()
   + getStateMachine()
   + getName()
   + requiresClient()
   + requiresComponent()
   + onEntry()
   + onExit()
   + executeOnEntry()
   + executeOnExit()
   # runtimeConfigure()
   # postEvent()
   # postEvent()
   # getCurrentState()
   # dispose()
   #getNode()
   # getLogger()
    - onOrthogonalAllocation()
                  Δ
   smacc2::SmaccAsyncClient
               Behavior
   - onEntryThread
   - on Exit Thread

    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::CbNav2ZClientBehaviorBase
# nav2zClient
# navigationCallback
# navigationResult
# goalHandleFuture
+ ~CbNav2ZClientBehaviorBase()
+ onOrthogonalAllocation()
# sendGoal()
# cancelGoal()
# isOwnActionResponse()
# onNavigationResult()
# onNavigationActionSuccess()
# onNavigationActionAbort()
    cl_nav2z::CbNavigateNext
              Waypoint
    # waypointsNavigator
    # options
    # navigationCallback
    + CbNavigateNextWaypoint()
    + ~CbNavigateNextWaypoint()
    + onEntry()
    + onExit()
                  Δ
  cl nav2z::CbNavigateNext
        WaypointUntilReached

    goalWaypointName

  - postEvGoalWaypointReached
  + CbNavigateNextWaypointUntil
  Reached()
  + ~CbNavigateNextWaypointUntil
  Reached()
  + onOrthogonalAllocation()
  + onEntry()
  + onExit()
  + onNavigationActionSuccess()
```