

```

    {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()
    }

```