## smacc2::ISmaccClient

# components_
- stateMachine_
- orthogonal_

+ ISmaccClient()
+ ~ISmaccClient()
+ onInitialize()
+ getName()
+ getComponent()
+ getComponent()
+ getComponent()
+ getType()
+ getStateMachine()
+ connectSignal()
+ requiresClient()
+ getComponents()
+ iterateComponents()
+ postEvent()
+ postEvent()
# onOrthogonalAllocation()
# createComponent()
# createNamedComponent()
# getNode()
# getLogger()
- initialize()
- setStateMachine()
- setOrthogonal()

## smacc2::client_bases ::ISmaccActionClient

# name_

+ ISmaccActionClient()
+ ~ISmaccActionClient()
+ getNamespace()
+ cancelGoal()
+ getClientBase()
+ getName()

## smacc2::client_bases ::SmaccActionClientBase < ActionType >

+ action_endpoint_
+ lastRequest_
+ lastCancelResponse_
+ onSucceeded_
+ onAborted_
+ onCancelled_
+ postSuccessEvent
+ postAbortedEvent
+ postCancelledEvent
+ postFeedbackEvent
+ feedback_cb
# client_

+ SmaccActionClientBase()
+ SmaccActionClientBase()
+ ~SmaccActionClientBase()
+ getClientBase()
+ onInitialize()
+ waitForServer()
+ postResultEvent()
+ onOrthogonalAllocation()
+ onSucceeded()
+ onSucceeded()
+ onAborted()
+ onAborted()
+ onCancelled()
+ onCancelled()
+ cancelGoal()
+ sendGoal()
+ getEventLabel()
# onFeedback()
# onResult()

< nav2_msgs::action ::NavigateToPose >

## smacc2::client_bases ::SmaccActionClientBase < nav2_msgs::action::NavigateTo Pose >

+ action_endpoint_
+ lastRequest_
+ lastCancelResponse_
+ onSucceeded_
+ onAborted_
+ onCancelled_
+ postSuccessEvent
+ postAbortedEvent
+ postCancelledEvent
+ postFeedbackEvent
+ feedback_cb
# client_

+ SmaccActionClientBase()
+ SmaccActionClientBase()
+ ~SmaccActionClientBase()
+ getClientBase()
+ onInitialize()
+ waitForServer()
+ postResultEvent()
+ onOrthogonalAllocation()
+ onSucceeded()
+ onSucceeded()
+ onAborted()
+ onAborted()
+ onCancelled()
+ onCancelled()
+ cancelGoal()
+ sendGoal()
+ getEventLabel()
# onFeedback()
# onResult()

## cl_nav2z::ClNav2Z

+ ClNav2Z()
+ ~ClNav2Z()