```
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
# robotPose
# robotPoseTimer
# recordPointDistanceThreshold_
# recordAngularDistanceThreshold
# clearPointDistanceThreshold_
# clearAngularDistanceThreshold_
# odomFrame_
# odomTopicName_
# publishMessages
# baseTrajectory_
# workingMode_
# pathStack_
# pathInfos_
# aggregatedStackPathMsg_
# strategy_
# currentMotionGoal_
# currentPathName_
# param_callback_handle_
# m_mutex
+ CpOdomTracker()
+ processNewPose()
+ odomMessageCallback()
+ update()
+ setWorkingMode()
+ setPublishMessages()
+ pushPath()
+ pushPath()
+ popPath()
+ clearPath()
+ setStartPoint()
+ setStartPoint()
+ setCurrentMotionGoal()
+ setCurrentPathName()
+ getCurrentMotionGoal()
+ getPath()
+ logStateString()
+ updateParameters()
+ setOdomFrame()
# onInitialize()
# updateConfiguration()
# rtPublishPaths()
# updateRecordPath()
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updateClearPath()

parametersCallback()

updateAggregatedStackPath()