```
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()
```

+ onSucessCallback()

+ onExit()