

```

    {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()
}

```