

| smacc2::ISmaccComponent   |
|---|
| # stateMachine_<br># owner_   |
| + ISmaccComponent()<br>+ ~ISmaccComponent()<br>+ getName()<br># onInitialize()<br># postEvent()<br># postEvent()<br># onOrthogonalAllocation()<br># requiresComponent()<br># requiresComponent()<br># requiresClient()<br># createSiblingComponent()<br># createSiblingNamedComponent()<br># getNode()<br># getLogger()<br># getStateMachine()<br>- initialize()<br>- setStateMachine() |



| cl_nav2z::odom_tracker<br>::CpOdomTracker   |
|---|
| # robotBasePathPub_<br># robotBasePathStackedPub_<br># odomSub_<br># recordPointDistanceThreshold_<br># recordAngularDistanceThreshold_<br># clearPointDistanceThreshold_<br># clearAngularDistanceThreshold_<br># odomFrame_<br># odomTopicName_<br># publishMessages<br># baseTrajectory_<br># workingMode_<br># pathStack_<br># pathInfos_<br># aggregatedStackPathMsg_<br># subscribeToOdometryTopic_<br># currentMotionGoal_<br># currentPathName_<br># m_mutex_                 |
| + CpOdomTracker()<br>+ processOdometryMessage()<br>+ setWorkingMode()<br>+ setPublishMessages()<br>+ pushPath()<br>+ pushPath()<br>+ popPath()<br>+ clearPath()<br>+ setStartPoint()<br>+ setStartPoint()<br>+ setCurrentMotionGoal()<br>+ setCurrentPathName()<br>+ getCurrentMotionGoal()<br>+ getPath()<br>+ logStateString()<br># onInitialize()<br># updateConfiguration()<br># rtPublishPaths()<br># updateRecordPath()<br># updateClearPath()<br># updateAggregatedStackPath() |