```
{smacc::ISmaccComponent
|# stateMachine_
# owner_
|+ ISmaccComponent()
+ ~ISmaccComponent()
+ getName()
# initialize()
# setStateMachine()
# postEvent()
# postEvent()
# onOrthogonalAllocation()
# requiresComponent()
# requiresClient()
# onInitialize()
# createSiblingComponent()
# createSiblingNamedComponent()
}
```

```
{cl_move_base_z::odom
      _tracker::OdomTracker
|# paramServer_
# f
# robotBasePathPub_
# robotBasePathStackedPub_
# odomSub_
# recordPointDistanceThreshold_
# recordAngularDistanceThreshold_
# clearPointDistanceThreshold_
# clearAngularDistanceThreshold_
# odomFrame_
# publishMessages
# baseTrajectory_
# workingMode_
# pathStack_
# aggregatedStackPathMsg_
# subscribeToOdometryTopic_
# currentPathTagName_
# m_mutex_
|+ OdomTracker()
+ processOdometryMessage()
+ setWorkingMode()
+ setPublishMessages()
+ pushPath()
+ popPath()
+ clearPath()
+ setStartPoint()
+ setStartPoint()
+ getPath()
+ logStateString()
+ getStackedPaths()
# reconfigCB()
# rtPublishPaths()
# updateRecordPath()
# updateClearPath()
# updateAggregatedStackPath()
}
```