```
{smacc::ISmaccClientBehavior
|- stateMachine_
- currentState
- currentOrthogonal
|+ ISmaccClientBehavior()
+ ~ISmaccClientBehavior()
+ getStateMachine()
+ getName()
+ requiresClient()
+ requiresComponent()
+ getNode()
# runtimeConfigure()
# onEntry()
# onExit()
# postEvent()
# postEvent()
# getCurrentState()
# executeOnEntry()
# executeOnExit()
# dispose()
- onOrthogonalAllocation()
                              }
```

```
{smacc::SmaccAsyncClientBehavior
|- onEntryThread_
- onExitThread_
- postFinishEventFn_
- postSuccessEventFn_
- postFailureEventFn_
- onFinished_
- onSuccess_
- onFailure_
|+ onOrthogonalAllocation()
+ ~SmaccAsyncClientBehavior()
+ onSuccess()
+ onFinished()
+ onFailure()
# executeOnEntry()
# executeOnExit()
# postSuccessEvent()
# postFailureEvent()
# dispose()
                      }
```

```
{cl_move_base_z::CbMoveBase
          ClientBehaviorBase
|# moveBaseClient_
# visualizationMarkersPub_
|+ onOrthogonalAllocation()
- propagateSuccessEvent()
- propagateFailureEvent()
                  }
```

```
{smacc::ISmaccUpdatable
|- periodDuration_
- lastUpdate_
|+ ISmaccUpdatable()
+ ISmaccUpdatable()
+ executeUpdate()
+ setUpdatePeriod()
# update()
              }
```

```
{cl_move_base_z::CbUndoPath
          Backwards2
|- goal_
- odomTracker_
- listener
- robotPose_
- goalLinePassed_
- initial_plane_side_
- triggerThreshold_
- postVirtualLinePassed_
|+ CbUndoPathBackwards2()
+ onEntry()
+ onExit()
+ update()
+ onOrthogonalAllocation()
- publishMarkers()
- evalPlaneSide()
                  }
```