

```

    {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()
}

```