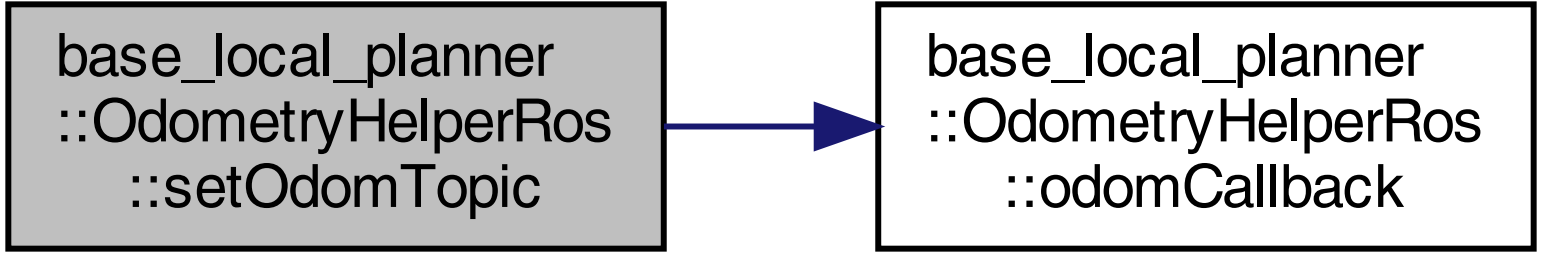
base_local_planner
::OdometryHelperRos
::setOdomTopic
base_local_planner
::OdometryHelperRos
::odomCallback