

base\_local\_planner  
::TrajectoryCostFunction



```
graph BT; A["base_local_planner::OscillationCostFunction"] --> B["base_local_planner::TrajectoryCostFunction"]
```

The diagram consists of two rectangular boxes. The top box is white with a black border and contains the text 'base\_local\_planner' followed by '::TrajectoryCostFunction' on the next line. The bottom box is gray with a black border and contains the text 'base\_local\_planner' followed by '::OscillationCostFunction' on the next line. A blue arrow points vertically from the top of the bottom box to the bottom of the top box, indicating an inheritance or specialization relationship.

base\_local\_planner  
::OscillationCostFunction