

costmap_2d::Costmap2DROS
::getRobotFootprintPolygon

```
graph LR; A["costmap_2d::Costmap2DROS  
::getRobotFootprintPolygon"] --> B["costmap_2d::toPolygon"]; B --> C["costmap_2d::toPoint32"]
```

costmap_2d::toPolygon

costmap_2d::toPoint32