## costmap\_2d::Costmap2D # size\_x\_ # size\_y # resolution # origin\_x\_ # origin\_y # costmap # default\_value\_ - access + Costmap2D() + Costmap2D() + operator=() + copyCostmapWindow() + Costmap2D() + ~Costmap2D() + getCost() + setCost() + mapToWorld() + worldToMap() and 23 more. # copyMapRegion() # deleteMaps() # resetMaps() # initMaps() # raytraceLine() - bresenham2D() sign() costmap\_2d::CostmapLayer # has\_extra\_bounds extra\_min\_x extra\_max\_x\_ - extra\_min\_y\_ base local planner extra\_max\_y ::WavefrontMapAccessor + CostmapLayer() - map + isDiscretized() - outer radius + matchSize() + WavefrontMapAccessor() + clearArea() + ~WavefrontMapAccessor() + addExtraBounds() # updateWithTrueOverwrite() + synchronize() # updateWithOverwrite() # updateWithMax() # updateWithAddition() # touch() # useExtraBounds() costmap\_2d::ObstacleLayer # transformed\_footprint\_ # footprint\_clearing enabled # global\_frame\_ # max\_obstacle\_height\_ costmap\_2d::StaticLayer # projector # observation\_subscribers\_ global\_frame\_ # observation\_notifiers\_ map\_frame\_ # observation\_buffers\_ subscribe\_to\_updates\_ # marking\_buffers\_ - map\_received # clearing\_buffers - has\_updated\_data\_ # static\_clearing\_observations\_ - X # static marking observations - y\_ # rolling window - width # dsrv height # combination\_method\_ track\_unknown\_space\_ and 8 more... + ObstacleLayer() + ~ObstacleLayer() + StaticLayer() + onInitialize() + ~StaticLayer() + updateBounds() + onInitialize() + updateCosts() + activate() + activate() + deactivate() + deactivate() + reset() + reset() + updateBounds() + laserScanCallback() + updateCosts() + laserScanValidInfCallback() + matchSize() + pointCloudCallback() incomingMap() + pointCloud2Callback() - incomingUpdate() + addStaticObservation() - reconfigureCB() + clearStaticObservations() interpretValue() # setupDynamicReconfigure() # getMarkingObservations() # getClearingObservations() # raytraceFreespace() # updateRaytraceBounds() # updateFootprint() - reconfigureCB() costmap\_2d::VoxelLayer voxel\_dsrv\_ publish\_voxel\_ voxel\_pub\_ - voxel\_grid z resolution origin\_z unknown\_threshold\_ mark\_threshold\_ - size\_z - clearing\_endpoints\_pub\_ - clearing\_endpoints\_

+ VoxelLayer() + ~VoxelLayer() + onlnitialize() + updateBounds() + updateOrigin() + isDiscretized() + matchSize() + reset()

# resetMaps()
- reconfigureCB()
- clearNonLethal()
- raytraceFreespace()
- worldToMap3DFloat()
- worldToMap3D()
- mapToWorld3D()

- dist()

# setupDynamicReconfigure()