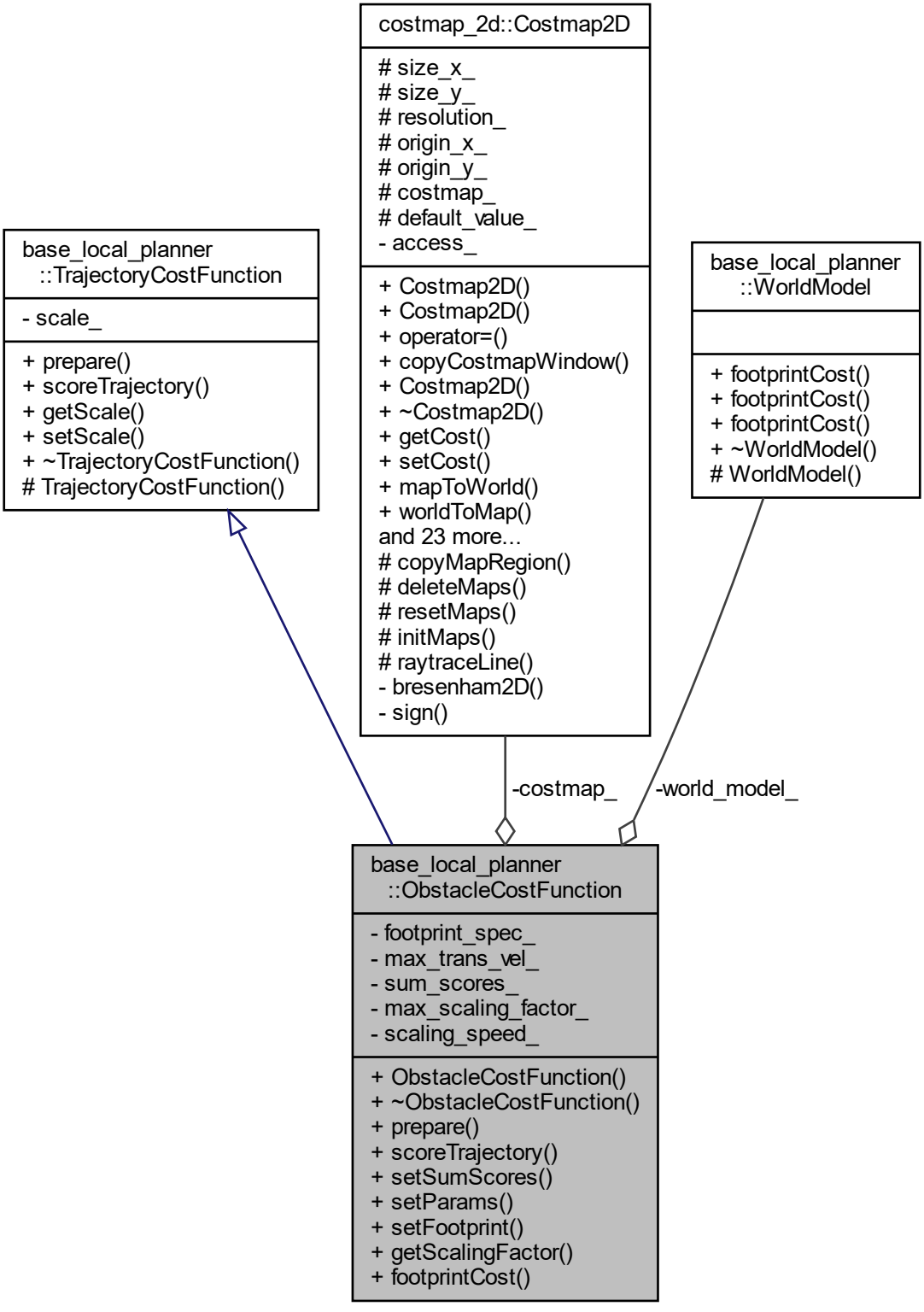
costmap_2d::Costmap2D
size_x_
size_y_
resolution_
origin_x_
origin_y_
costmap_
default_value_
- access_
+ Costmap2D()
+ Costmap2D()
+ operator=()
+ copyCostmapWindow()
+ Costmap2D()
+ ~Costmap2D()
+ getCost()
+ setCost()
+ mapToWorld()
+ worldToMap()
and 23 more...
copyMapRegion()
deleteMaps()
resetMaps()
initMaps()
raytraceLine()
- bresenham2D()
- sign()
base_local_planner ::TrajectoryCostFunction
- scale_
+ prepare()
+ scoreTrajectory()
+ getScale()
+ setScale()
+ ~TrajectoryCostFunction()
# TrajectoryCostFunction()
base_local_planner ::WorldModel
+ footprintCost()
+ footprintCost()
+ footprintCost()
+ ~WorldModel()
# WorldModel()
-costmap_
-world_model_
base_local_planner ::ObstacleCostFunction
- footprint_spec_
- max_trans_vel_
- sum_scores_
- max_scaling_factor_
- scaling_speed_
+ ObstacleCostFunction()
+ ~ObstacleCostFunction()
+ prepare()
+ scoreTrajectory()
+ setSumScores()
+ setParams()
+ setFootprint()
+ getScalingFactor()
+ footprintCost()