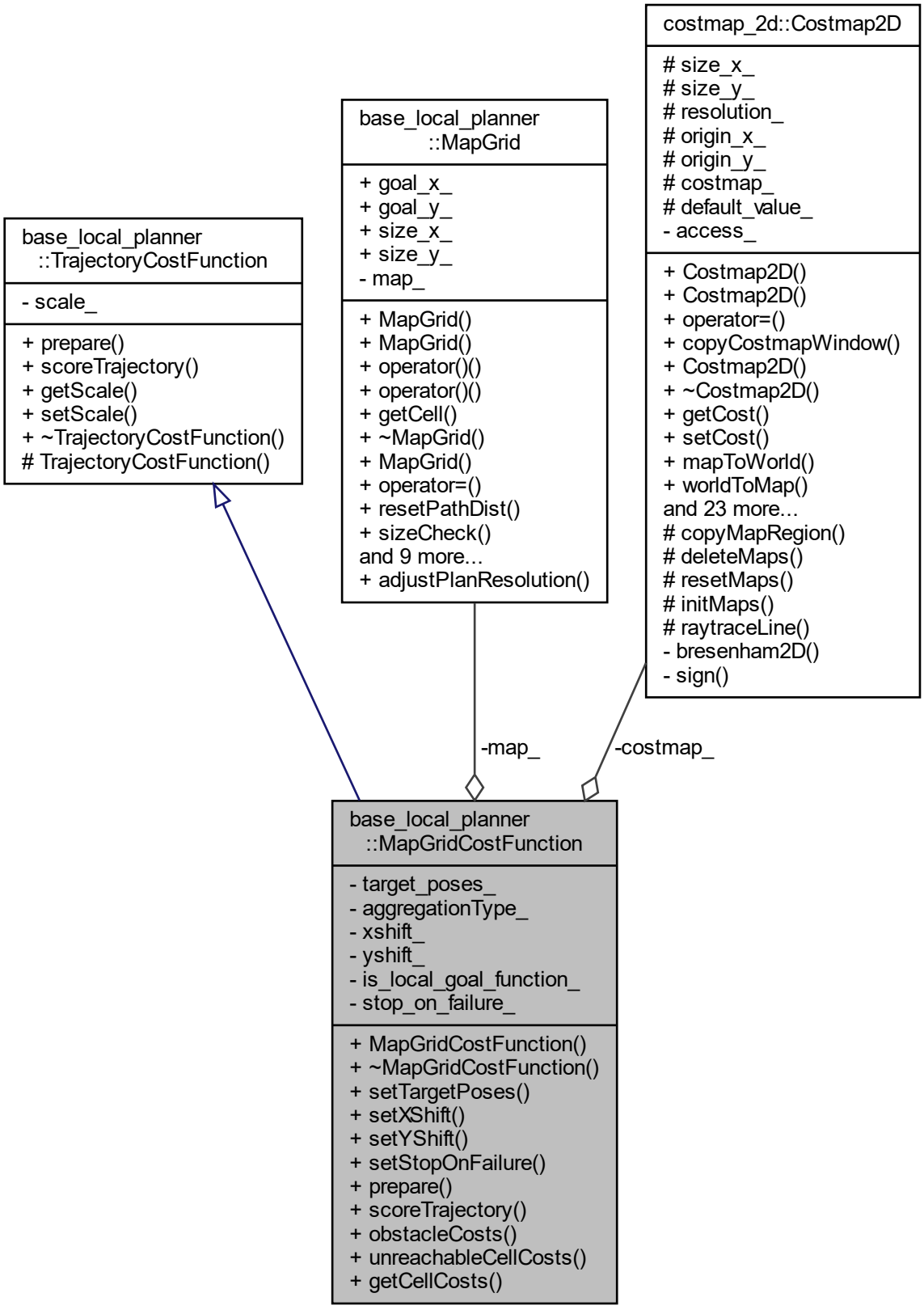
base_local_planner
::TrajectoryCostFunction
- scale_
+ prepare()
+ scoreTrajectory()
+ getScale()
+ setScale()
+ ~TrajectoryCostFunction()
# TrajectoryCostFunction()
base_local_planner
::MapGrid
+ goal_x_
+ goal_y_
+ size_x_
+ size_y_
- map_
+ MapGrid()
+ MapGrid()
+ operator()()
+ operator()()
+ getCell()
+ ~MapGrid()
+ MapGrid()
+ operator=()
+ resetPathDist()
+ sizeCheck()
and 9 more...
+ adjustPlanResolution()
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()
-map_
-costmap_
base_local_planner
::MapGridCostFunction
- target_poses_
- aggregationType_
- xshift_
- yshift_
- is_local_goal_function_
- stop_on_failure_
+ MapGridCostFunction()
+ ~MapGridCostFunction()
+ setTargetPoses()
+ setXShift()
+ setYShift()
+ setStopOnFailure()
+ prepare()
+ scoreTrajectory()
+ obstacleCosts()
+ unreachableCellCosts()
+ getCellCosts()