nav core::BaseLocalPlanner + computeVelocityCommands() + isGoalReached() + setPlan() + initialize() + ~BaseLocalPlanner() # BaseLocalPlanner() dwa local planner:: **DWAPlannerROS** - tf - g plan pub - I plan pub - planner util - dp costmap ros - dsrv - default config - setup - current pose latchedStopRotateController initialized - odom helper - odom topic + DWAPlannerROS() + initialize() + ~DWAPlannerROS() + computeVelocityCommands() + dwaComputeVelocityCommands() + setPlan() + isGoalReached() + isInitialized() reconfigureCB() publishLocalPlan() publishGlobalPlan()