base_local_planner ::LocalPlannerLimits + max vel trans + min vel trans + max vel x base local planner + min vel x ::TrajectorySampleGenerator + max vel y + min vel y + max vel theta + hasMoreTrajectories() + min vel theta + nextTrajectory() + acc lim x + ~TrajectorySampleGenerator() + acc lim y # TrajectorySampleGenerator() and 8 more... + LocalPlannerLimits() + LocalPlannerLimits() + ~LocalPlannerLimits() + getAccLimits() #limits base local planner ::SimpleTrajectoryGenerator # next sample index # sample params # pos # vel # continued acceleration # discretize by time # sim time # sim_granularity_ # angular sim granularity # use dwa # sim period + SimpleTrajectoryGenerator() + ~SimpleTrajectoryGenerator() + initialise() + initialise() + setParameters() + hasMoreTrajectories() + nextTrajectory() + generateTrajectory() + computeNewPositions() + computeNewVelocities()