```
                    ┌─────────────────────────────────┐
                    │    nav_core::BaseLocalPlanner    │
                    ├─────────────────────────────────┤
                    │                                  │
                    ├─────────────────────────────────┤
                    │ + computeVelocityCommands()      │
                    │ + isGoalReached()                │
                    │ + setPlan()                      │
                    │ + initialize()                   │
                    │ + ~BaseLocalPlanner()            │
                    │ # BaseLocalPlanner()             │
                    └─────────────────────────────────┘
```

base_local_planner ::TrajectoryPlannerROS

- world_model_
- tc_
- costmap_ros_
- costmap_
- map_viz_
- tf_
- global_frame_
- max_sensor_range_
- base_odom_
- robot_base_frame_
and 26 more...

+ TrajectoryPlannerROS()
+ TrajectoryPlannerROS()
+ initialize()
+ ~TrajectoryPlannerROS()
+ computeVelocityCommands()
+ setPlan()
+ isGoalReached()
+ checkTrajectory()
+ scoreTrajectory()
+ isInitialized()
+ getPlanner()
- reconfigureCB()
- rotateToGoal()
- stopWithAccLimits()
- loadYVels()
- sign()

dwa_local_planner:: DWAPlannerROS

- tf_
- g_plan_pub_
- l_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()