```
nav core::BaseGlobalPlanner
+ makePlan()
+ makePlan()
+ initialize()
+ ~BaseGlobalPlanner()
# BaseGlobalPlanner()
      navfn::NavfnROS
  # costmap
  # planner
  # plan_pub
  # potarr_pub_
  # initialized
  # allow unknown
  # visualize_potential_
  planner_window_x_
  planner_window_y_

    default tolerance_

  - mutex
  make_plan_srv_
  global_frame
  + NavfnROS()
  + NavfnROS()
  + NavfnROS()
  + initialize()
  + initialize()
  + makePlan()
  + makePlan()
  + computePotential()
  + getPlanFromPotential()
  + getPointPotential()
  + validPointPotential()
  + validPointPotential()
  + publishPlan()
  + ~NavfnROS()
  + makePlanService()
  sq_distance()
  mapToWorld()
  clearRobotCell()
 navfn::NavfnWithCostmap

    cmap

  make_plan_service
  pose_sub_
  + NavfnWithCostmap()
  + makePlanService()
```

poseCallback()