```
# size_x_
                               # size_y
  costmap_2d::Layer
                               # resolution
# layered_costmap_
                               # origin_x
                               # origin_y
# current
# enabled
                               # costmap
# name_
                               # default_value_
#tf
                               - access
footprint_spec_
                               + Costmap2D()
+ Layer()
                               + Costmap2D()
+ initialize()
                               + operator=()
                               + copyCostmapWindow()
+ updateBounds()
+ updateCosts()
                               + Costmap2D()
                               + ~Costmap2D()
+ deactivate()
+ activate()
                               + getCost()
+ reset()
                               + setCost()
+ ~Layer()
                               + mapToWorld()
+ isCurrent()
                               + worldToMap()
+ matchSize()
                               and 23 more.
+ getName()
                               # copyMapRegion()
                               # deleteMaps()
+ getFootprint()
                               # resetMaps()
+ onFootprintChanged()
# onlnitialize()
                               # initMaps()
                               # raytraceLine()
                               bresenham2D()
                               - sign()
             costmap_2d::CostmapLayer
             # has_extra_bounds_
             - extra_min_x
             extra_max_x
             extra_min_y
             - extra max
             + CostmapLayer()
             + isDiscretized()
             + matchSize()
             + clearArea()
             + addExtraBounds()
             # updateWithTrueOverwrite()
             # updateWithOverwrite()
             # updateWithMax()
             # updateWithAddition()
             # touch()
             # useExtraBounds()
                           Δ
               costmap_2d::StaticLayer
               - global_frame
               - map_frame
               - subscribe_to
                              updates
               - map_received
               has_updated_data_
               - X
               - y_
- width
               - height

    track_unknown_space

               and 8 more.
               + StaticLayer()
               + ~StaticLayer()
               + onlnitialize()
               + activate()
               + deactivate()
               + reset()
               + updateBounds()
               + updateCosts()
               + matchSize()
               incomingMap()
               - incomingUpdate()
               reconfigureCB()
               - interpretValue()
```

costmap_2d::Costmap2D