costmap_2d::Costmap2D

\# size_x_
\# size_y_
\# resolution_
\# origin_x_
\# origin_y_
\# costmap_
\# default_value_
- access_

+ Costmap2D()
+ Costmap2D()
+ operator=()
+ copyCostmapWindow()
+ Costmap2D()
+ ~Costmap2D()
+ getCost()
+ setCost()
+ mapToWorld()
+ worldToMap()
and 23 more...
\# copyMapRegion()
\# deleteMaps()
\# resetMaps()
\# initMaps()
\# raytraceLine()
- bresenham2D()
- sign()

string

costmap_2d::Costmap2DPublisher

- node
- x0_
- xn_
- y0_
- yn_
- saved_origin_x_
- saved_origin_y_
- active_
- always_send_full_costmap_
- costmap_pub_
- costmap_update_pub_
- grid_
- cost_translation_table_

+ Costmap2DPublisher()
+ ~Costmap2DPublisher()
+ updateBounds()
+ publishCostmap()
+ active()
- prepareGrid()
- onNewSubscription()

costmap_2d::LayeredCostmap

- rolling_window_
- current_
- minx_
- miny_
- maxx_
- maxy_
- bx0_
- bxn_
- by0_
- byn_
and 6 more...

+ LayeredCostmap()
+ ~LayeredCostmap()
+ updateMap()
+ getGlobalFrameID()
+ resizeMap()
+ getUpdatedBounds()
+ isCurrent()
+ getCostmap()
+ isRolling()
+ isTrackingUnknown()
and 9 more...

-global_frame_   -global_frame_   -costmap_   -costmap_

\#global_frame_
\#name_
\#robot_base_frame_

costmap_2d::Costmap2DROS

\# tf_
\# transform_tolerance_
- map_update_thread_shutdown_
- stop_updates_
- initialized_
- stopped_
- robot_stopped_
- map_update_thread_
- timer_
- last_publish_
- publish_cycle
- plugin_loader_
and 9 more...

+ Costmap2DROS()
+ ~Costmap2DROS()
+ start()
+ stop()
+ pause()
+ resume()
+ updateMap()
+ resetLayers()
+ isCurrent()
+ isStopped()
and 13 more...
- readFootprintFromConfig()
- loadOldParameters()
- warnForOldParameters()
- checkOldParam()
- copyParentParameters()
- reconfigureCB()
- movementCB()
- mapUpdateLoop()

-global_frame_
-robot_base_frame_

-publisher_

\#layered_costmap_

-controller_costmap
ros
-planner_costmap_ros_

move_base::MoveBase

- tf_
- as_
- tc_
- planner_
- recovery_behaviors_
- recovery_index_
- global_pose_
- planner_frequency_
- controller_frequency_
- inscribed_radius_
and 45 more...

+ MoveBase()
+ ~MoveBase()
+ executeCycle()
- clearCostmapsService()
- planService()
- makePlan()
- loadRecoveryBehaviors()
- loadDefaultRecoveryBehaviors()
- clearCostmapWindows()
- publishZeroVelocity()
- resetState()
- goalCB()
- planThread()
and 7 more...