costmap_2d::Layer

layered_costmap_
current_
enabled_
name_
tf_
- footprint_spec_

+ Layer()
+ initialize()
+ updateBounds()
+ updateCosts()
+ deactivate()
+ activate()
+ reset()
+ ~Layer()
+ isCurrent()
+ matchSize()
+ getName()
+ getFootprint()
+ onFootprintChanged()
# onInitialize()

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()

costmap_2d::CostmapLayer

has_extra_bounds_
- extra_min_x_
- extra_max_x_
- extra_min_y_
- extra_max_y_

+ CostmapLayer()
+ isDiscretized()
+ matchSize()
+ clearArea()
+ addExtraBounds()
# updateWithTrueOverwrite()
# updateWithOverwrite()
# updateWithMax()
# updateWithAddition()
# touch()
# useExtraBounds()

costmap_2d::ObstacleLayer

transformed_footprint_
footprint_clearing
enabled
global_frame_
max_obstacle_height_
projector_
observation_subscribers_
observation_notifiers_
observation_buffers_
marking_buffers_
clearing_buffers_
static_clearing_observations_
static_marking_observations_
rolling_window_
dsrv_
combination_method_

+ ObstacleLayer()
+ ~ObstacleLayer()
+ onInitialize()
+ updateBounds()
+ updateCosts()
+ activate()
+ deactivate()
+ reset()
+ laserScanCallback()
+ laserScanValidInfCallback()
+ pointCloudCallback()
+ pointCloud2Callback()
+ addStaticObservation()
+ clearStaticObservations()
# setupDynamicReconfigure()
# getMarkingObservations()
# getClearingObservations()
# raytraceFreespace()
# updateRaytraceBounds()
# updateFootprint()
- reconfigureCB()

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()
+ onInitialize()
+ activate()
+ deactivate()
+ reset()
+ updateBounds()
+ updateCosts()
+ matchSize()
- incomingMap()
- incomingUpdate()
- reconfigureCB()
- interpretValue()

costmap_2d::VoxelLayer

- voxel_dsrv_
- publish_voxel_
- voxel_pub_
- voxel_grid_
- z_resolution_
- origin_z_
- unknown_threshold_
- mark_threshold_
- size_z_
- clearing_endpoints_pub_
- clearing_endpoints_

+ VoxelLayer()
+ ~VoxelLayer()
+ onInitialize()
+ updateBounds()
+ updateOrigin()
+ isDiscretized()
+ matchSize()
+ reset()
# setupDynamicReconfigure()
# resetMaps()
- reconfigureCB()
- clearNonLethal()
- raytraceFreespace()
- worldToMap3DFloat()
- worldToMap3D()
- mapToWorld3D()
- dist()