## nav core::BaseGlobalPlanner + makePlan() + makePlan() + initialize() + ~BaseGlobalPlanner() # BaseGlobalPlanner() global planner::GlobalPlanner # costmap navfn::NavfnROS # frame id # plan pub # costmap # initialized # planner # allow unknown # plan pub - planner window x # potarr pub - planner\_window\_y\_ # initialized - default tolerance # allow unknown - mutex\_ # visualize potential - make plan srv - planner window x - p calc - planner window\_y\_ planner - default tolerance - path maker - mutex - orientation filter make\_plan\_srv - publish potential - global frame and 11 more... + NavfnROS() + GlobalPlanner() + NavfnROS() + GlobalPlanner() + NavfnROS() + ~GlobalPlanner() + initialize() + initialize() + initialize() + initialize() + makePlan() + makePlan() + makePlan() + makePlan() + computePotential() + computePotential() + getPlanFromPotential() + getPlanFromPotential() + getPointPotential() + getPointPotential() + validPointPotential() + validPointPotential() + validPointPotential() + validPointPotential() + publishPlan() + publishPlan() + ~NavfnROS() + makePlanService() + makePlanService() - mapToWorld() - sq distance() - worldToMap() - mapToWorld() - clearRobotCell() clearRobotCell() - publishPotential() - outlineMap() reconfigureCB() global planner::PlannerWith navfn::NavfnWithCostmap Costmap cmap - cmap - make plan service - make plan service - pose sub - pose sub + NavfnWithCostmap() + PlannerWithCostmap()

+ makePlanService()

poseCallback()

+ makePlanService()

poseCallback()

carrot planner::CarrotPlanner

- costmap\_ros\_

- world model

+ CarrotPlanner()

+ CarrotPlanner()

- min\_dist\_from robot

- step size

costmap

- initialized

+ initialize()

+ makePlan()

footprintCost()