```
voxel_grid::VoxelGrid
                           - size x
                           size_y_
                           - size z
                           - data

    costmap

base local planner
                           + VoxelGrid()
  ::WorldModel
                           + ~VoxelGrid()
                           + resize()
                           + reset()
+ footprintCost()
                           + getData()
+ footprintCost()
                           + markVoxel()
+ footprintCost()
                           + markVoxelInMap()
+ ~WorldModel()
                           + clearVoxel()
# WorldModel()
                           + clearVoxelColumn()
                           + clearVoxelInMap()
                           and 12 more...
                           + numBits()
                           + getVoxel()
                           - bresenham3D()
                           - sign()

    max()

                                obstacle_grid_
        base local planner
               ::VoxelGridModel
        xy_resolution_

    z resolution

        origin_x_
        - origin y
        - origin z
        - max z
        - sq obstacle range
        + VoxelGridModel()
        + ~VoxelGridModel()
        + footprintCost()
        + updateWorld()
        + getPoints()
        + footprintCost()
        + footprintCost()
        + footprintCost()
        lineCost()
        - pointCost()
        removePointsInScanBoundry()
        worldToMap3D()
        worldToMap2D()
        mapToWorld3D()

    mapToWorld2D()

    dist()

        insert()
```