```
costmap 2d::Costmap2D
             # size_x_
             # size_y_
             # resolution
             # origin_x_
                                              base local planner
             # origin_y_
                                                ::LocalPlannerLimits
             # costmap
             # default_value_
                                              + max vel trans
                                              + min vel trans
             - access
                                              + max vel x
             + Costmap2D()
                                              + min vel x
             + Costmap2D()
                                              + max vel y
string
             + operator=()
                                              + min vel y
             + copyCostmapWindow()
                                              + max_vel_theta
             + Costmap2D()
                                              + min_vel_theta
             + ~Costmap2D()
                                              + acc lim x
             + getCost()
                                              + acc lim y
             + setCost()
                                              and 8 more...
             + mapToWorld()
             + worldToMap()
                                              + LocalPlannerLimits()
                                              + LocalPlannerLimits()
             and 23 more...
             # copyMapRegion()
                                              + ~LocalPlannerLimits()
             # deleteMaps()
                                              + getAccLimits()
             # resetMaps()
             # initMaps()
             # raytraceLine()
             - bresenham2D()
             - sign()
          -global_frame_
                                         -default limits
                          -costmap
                                            -limits
             -name
               base_local_planner
                 ::LocalPlannerUtil
               - tf
               - global plan
               - limits configuration
               _mutex
               - setup

    initialized

               + reconfigureCB()
               + LocalPlannerUtil()
               + ~LocalPlannerUtil()
               + initialize()
               + getGoal()
               + setPlan()
               + getLocalPlan()
               + getCostmap()
               + getCurrentLimits()
               + getGlobalFrame()
```