```
nav core::BaseLocalPlanner
+ computeVelocityCommands()
+ isGoalReached()
+ setPlan()
+ initialize()
+ ~BaseLocalPlanner()
# BaseLocalPlanner()
base_local_planner
    ::TrajectoryPlannerROS

    world model

- tc

    costmap ros

    costmap

- map viz
- tf

    global frame

- max sensor range

    base odom

- robot base frame
and 26 more...
+ TrajectoryPlannerROS()
+ TrajectoryPlannerROS()
+ initialize()
+ ~TrajectoryPlannerROS()
+ computeVelocityCommands()
+ setPlan()
+ isGoalReached()
+ checkTrajectory()
+ scoreTrajectory()
+ isInitialized()
+ getPlanner()
- reconfigureCB()
rotateToGoal()
stopWithAccLimits()
loadYVels()

    sign()
```