```
nav core::BaseGlobalPlanner
+ makePlan()
+ makePlan()
+ initialize()
+ ~BaseGlobalPlanner()
# BaseGlobalPlanner()
             Δ
global planner::GlobalPlanner
# costmap
# frame id
# plan_pub
# initialized
# allow_unknown
planner_window_x_
- planner_window_y_
- default tolerance
mutex
- make plan srv
- p calc
- planner
- path maker
- orientation filter
- publish potential
and 11 more...
+ GlobalPlanner()
+ GlobalPlanner()
+ ~GlobalPlanner()
+ initialize()
+ initialize()
+ makePlan()
+ makePlan()
+ computePotential()
+ getPlanFromPotential()
+ getPointPotential()
+ validPointPotential()
+ validPointPotential()
+ publishPlan()
+ makePlanService()
mapToWorld()
worldToMap()
clearRobotCell()
publishPotential()
outlineMap()
reconfigureCB()
              Δ
global planner::PlannerWith
          Costmap

    cmap

 - make_plan_service_
 pose_sub_
 + PlannerWithCostmap()
```

+ makePlanService()- poseCallback()