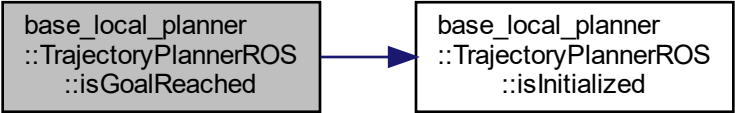


base_local_planner
::TrajectoryPlannerROS
::isGoalReached



```
graph LR; A["base_local_planner  
::TrajectoryPlannerROS  
::isGoalReached"] --> B["base_local_planner  
::TrajectoryPlannerROS  
::isInitialized"]
```

A diagram showing a transition from a goal reached state to an initialized state. It consists of two rectangular boxes connected by a blue arrow pointing from left to right. The left box has a light gray background and contains the text 'base_local_planner', '::TrajectoryPlannerROS', and '::isGoalReached'. The right box has a white background and contains the text 'base_local_planner', '::TrajectoryPlannerROS', and '::isInitialized'.

base_local_planner
::TrajectoryPlannerROS
::isInitialized