```
base local planner
    ::TrajectoryCostFunction

    scale

   + prepare()
   + scoreTrajectory()
   + getScale()
   + setScale()
   + ~TrajectoryCostFunction()
   # Trajectory CostFunction()
base local planner
    ::OscillationCostFunction
- strafe pos only
- strafe neg only
- strafing pos
- strafing neg
- rot pos only
- rot neg only
- rotating pos

    rotating neg

- forward pos only
- forward neg only
- forward pos
- forward neg
- oscillation reset dist
- oscillation reset angle
- prev stationary pos
+ OscillationCostFunction()
+ ~OscillationCostFunction()
+ scoreTrajectory()
+ prepare()
+ resetOscillationFlags()
+ updateOscillationFlags()
+ setOscillationResetDist()

    resetOscillationFlagslfPossible()

setOscillationFlags()
```