

base\_local\_planner  
::Trajectory

+ xv\_  
+ yv\_  
+ thetav\_  
+ cost\_  
+ time\_delta\_  
- x\_pts\_  
- y\_pts\_  
- th\_pts\_

+ Trajectory()  
+ Trajectory()  
+ getPoint()  
+ setPoint()  
+ addPoint()  
+ getEndpoint()  
+ resetPoints()  
+ getPointsSize()