BaseLocalPlanner move base z client ::backward local planner ::BackwardLocalPlanner - paramServer backwardsPlanPath costmapRos goalMarkerPublisher - k rho - k alpha - k betta - goalReached - initialPureSpinningStage pureSpinningMode - alpha offset betta offset yaw goal tolerance - xv goal tolerance - carrot distance - carrot\_angular distance - max linear x speed - max angular z speed currentPoseIndex + BackwardLocalPlanner() + ~BackwardLocalPlanner() + computeVelocityCommands() + isGoalReached() + setPlan() + initialize() + initialize() + initialize() reconfiaCB() createCarrotGoal() pureSpinningCmd() defaultBackwardCmd() publishGoalMarker()