



-max\_angular\_z\_speed  
-xy\_goal\_tolerance  
-yaw\_goal\_tolerance  
-k\_beta\_  
-k\_rho\_  
-carrot\_angular\_distance\_  
-beta\_offset  
-alpha\_offset  
-k\_alpha\_  
-carrot\_distance\_  
-  
...

-goalMarkerPublisher\_

-plan\_

-costmapRos\_

-currentPoseIndex\_

-goalReached\_

