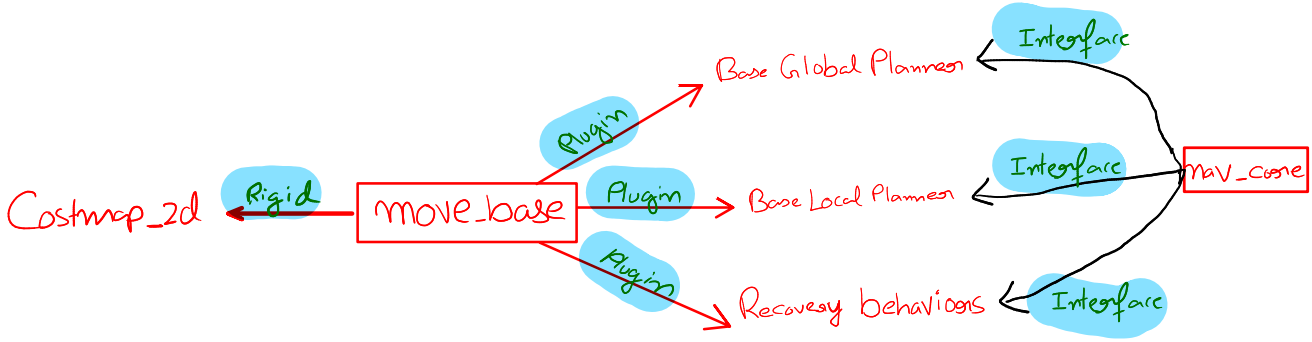

Nav_Core

① BaseLocalPlanner

- All local planners written as plugins for the navigation stack must adhere to this interface

Public Member Functions

virtual bool	**computeVelocityCommands** (geometry_msgs::Twist &cmd_vel)=0 Given the current position, orientation, and velocity of the robot, compute velocity commands to send to the base. More...
virtual void	**initialize** (std::string name, tf2_ros::Buffer *tf, costmap_2d::Costmap2DROS *costmap_ros)=0 Constructs the local planner. More...
virtual bool	**isGoalReached** ()=0 Check if the goal pose has been achieved by the local planner. More...
virtual bool	**setPlan** (const std::vector< geometry_msgs::PoseStamped > &plan)=0 Set the plan that the local planner is following. More...
virtual	**~BaseLocalPlanner** () Virtual destructor for the interface. More...