BaseLocalPlanner cl move_base_z::backward local planner::BackwardLocalPlanner paramServer backwardsPlanPath - costmapRos goalMarkerPublisher - k_rho - k_alpha - k betta - pure spinning allowed betta_error - linear mode rho error threshold goalReached initialPureSpinningStage pureSpinningMode enable_obstacle_checking - alpha offset - betta offset - yaw_goal_tolerance - xy goal tolerance - carrot distance carrot angular distance - max_linear_x_speed_ - max angular z speed currentCarrotPoseIndex waiting waitingTimeout waitingStamp + BackwardLocalPlanner() + ~BackwardLocalPlanner() + computeVelocityCommands() + isGoalReached() + setPlan() + initialize() + initialize() + initialize() reconfigCB() createCarrotGoal() pureSpinningCmd() defaultBackwardCmd() publishGoalMarker() computeCurrentEuclideanAnd AngularErrors() generateTrajectory() computeNewPositions()