

BaseLocalPlanner



cl\_move\_base\_z::pure  
\_spinning\_local\_planner  
::PureSpinningLocalPlanner

- costmapRos\_
- plan\_
- paramServer\_
- k\_beta\_
- goalReached\_
- currentPoseIndex\_
- yaw\_goal\_tolerance\_
- intermediate\_goal\_yaw\_tolerance\_
- max\_angular\_z\_speed\_

- + PureSpinningLocalPlanner()
- + ~PureSpinningLocalPlanner()
- + computeVelocityCommands()
- + isGoalReached()
- + setPlan()
- + initialize()
- + initialize()
- + initialize()
- reconfigCB()
- publishGoalMarker()