

BaseLocalPlanner



cl\_move\_base\_z::backward  
\_local\_planner::BackwardLocalPlanner

- paramServer\_
- f
- backwardsPlanPath\_
- costmapRos\_
- goalMarkerPublisher\_
- k\_rho\_
- k\_alpha\_
- k\_betta\_
- pure\_spinning\_allowed
- betta\_error
- linear\_mode\_rho\_error
- threshold\_
- goalReached
- initialPureSpinningStage\_
- straightBackwardsAndPure
- SpinningMode\_
- enable\_obstacle\_checking\_
- inGoalPureSpinningState\_
- alpha\_offset\_
- betta\_offset\_
- yaw\_goal\_tolerance\_
- xy\_goal\_tolerance\_
- carrot\_distance\_
- carrot\_angular\_distance\_
- divergenceDetectionLastCarrot
- LinearDistance\_
- max\_linear\_x\_speed\_
- max\_angular\_z\_speed\_
- currentCarrotPoseIndex\_
- waiting\_
- waitingTimeout\_
- waitingStamp\_

- + BackwardLocalPlanner()
- + ~BackwardLocalPlanner()
- + computeVelocityCommands()
- + isGoalReached()
- + setPlan()
- + initialize()
- + initialize()
- + initialize()
- reconfigCB()
- findInitialCarrotGoal()
- updateCarrotGoal()
- resamplePrecisePlan()
- straightBackwardsAndPure
- SpinCmd()
- defaultBackwardCmd()
- publishGoalMarker()
- computeCurrentEuclideanAnd
- AngularErrorsToCarrotGoal()
- checkCurrentPoseInGoalRange()
- resetDivergenceDetection()
- divergenceDetectionUpdate()
- checkCarrotHalfPlainConstraint()
- generateTrajectory()
- computeNewPositions()