BaseLocalPlanner cl move base z::backward local planner::BackwardLocalPlanner - paramServer backwardsPlanPath costmapRos - goalMarkerPublisher - k rho - k alpha - k betta goalReached initialPureSpinningStage pureSpinningMode alpha offset - betta offset - yaw goal tolerance - xy goal tolerance - carrot distance - carrot angular distance max_linear_x_speed_ - max angular z speed currentPoseIndex - waiting waitingTimeout waitingStamp + BackwardLocalPlanner() + ~BackwardLocalPlanner() + computeVelocityCommands() + isGoalReached() + setPlan() + initialize() + initialize() + initialize() reconfigCB() createCarrotGoal() pureSpinningCmd() defaultBackwardCmd() publishGoalMarker() generateTrajectory() computeNewPositions()