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() checkGoalReached() generateTrajectory() computeNewPositions()