

BaseLocalPlanner



cl_move_base_z::pure
_spinning_local_planner
::PureSpinningLocalPlanner

- costmapRos_
- goalMarkerPublisher_
- plan_
- k_betta_
- goalReached_
- currentPoseIndex_
- yaw_goal_tolerance_
- intermediate_goal_yaw_tolerance_
- max_angular_z_speed_

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