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()