BaseLocalPlanner cl move base z:: local planner::ForwardLocalPlanner costmapRos goalMarkerPublisher - k rho - k alpha - k betta - goalReached - alpha offset betta offset carrot distance carrot angular distance yaw goal tolerance - xy goal tolerance max angular z speed - max linear x speed currentPoseIndex - plan waiting waitingTimeout - waitingStamp + ForwardLocalPlanner() + ~ForwardLocalPlanner() + computeVelocityCommands() + isGoalReached() + setPlan() + initialize() + initialize() + initialize() publishGoalMarker() generateTrajectory() computeNewPositions()