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() generateTrajectory() computeNewPositions()