



-nh_

-name_

-backwardsPlanPath_

-costmapRos_
-goalMarkerPublisher
-planPub_
-tf_

-alpha_offset_
-beta_offset_
-carrot_angular_distance_
-carrot_distance_
-divergenceDetection
LastCarrotLinearDistance
-k_alpha_
-k_beta_
-k_rho_
-linear_mode_rho_
_error_threshold
-max_angular_
_z_speed_
...

-waitingTimeout_

-waitingStamp_

-enable_obstacle_checking
-goalReached_
-inGoalPureSpinningState
-initialPureSpinningStage
-straightBackwardsAndPure
SpinningMode_
-waiting_

-currentCarrotPoseIndex_

cl_nav2z::backward
_local_planner::BackwardLocal
Planner

- pure_spinning_allowed
_beta_error_
- max_linear_x_speed_
- yaw_goal_tolerance_
- xy_goal_tolerance_
- transform_tolerance_

+ BackwardLocalPlanner()
+ ~BackwardLocalPlanner()
+ configure()
+ activate()
+ deactivate()
+ cleanup()
+ setPlan()
+ computeVelocityCommands()
+ isGoalReached()
+ setSpeedLimit()
- updateParameters()
- findInitialCarrotGoal()
- updateCarrotGoal()
- resamplePrecisePlan()
- straightBackwardsAndPure
SpinCmd()
- clearMarkers()
- publishGoalMarker()
- computeCurrentEuclideanAnd
AngularErrorsToCarrotGoal()
- checkGoalReached()
- checkCurrentPoseInGoalRange()
- resetDivergenceDetection()
- divergenceDetectionUpdate()
- checkCarrotHalfPlainConstraint()
- generateTrajectory()
- computeNewPositions()

