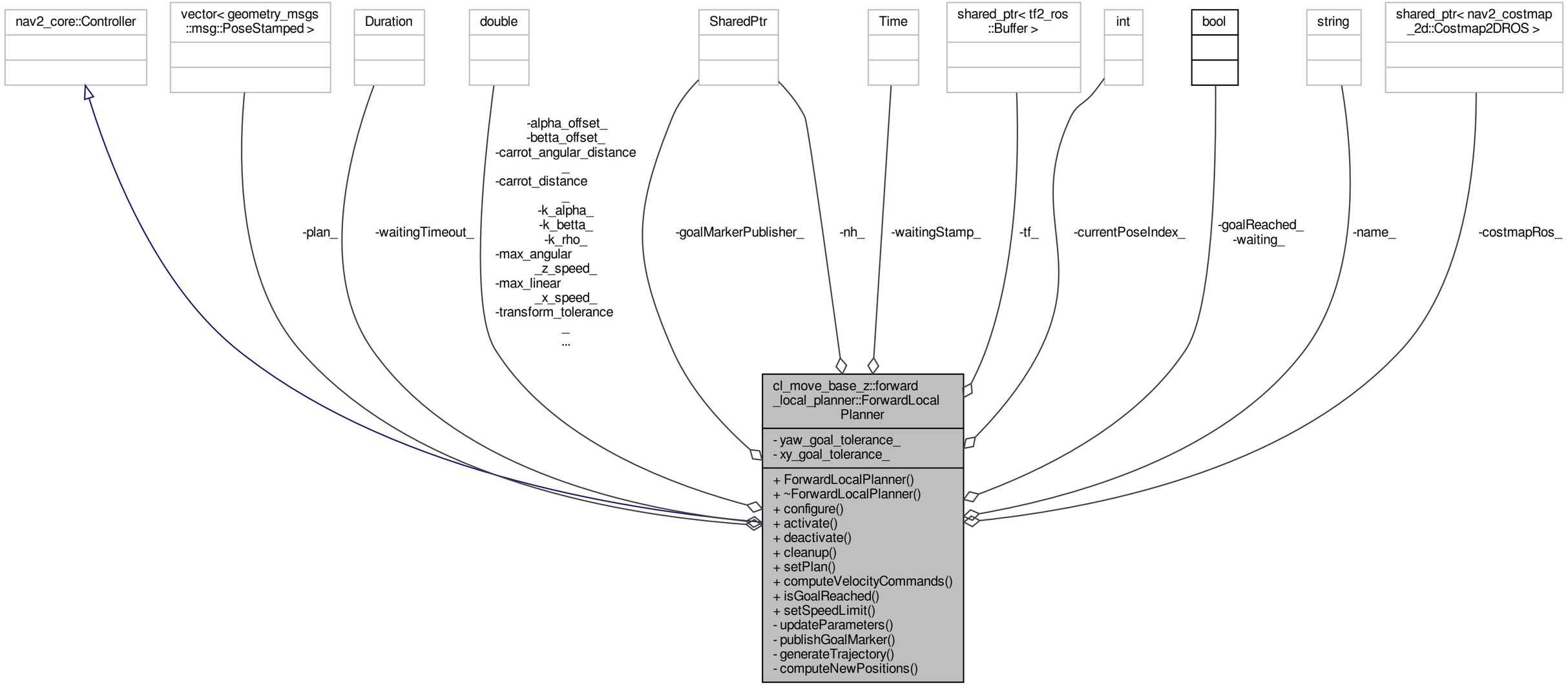
nav2_core::Controller
vector< geometry_msgs ::msg::PoseStamped >
Duration
double
SharedPtr
Time
shared_ptr< tf2_ros ::Buffer >
int
bool
string
shared_ptr< nav2_costmap _2d::Costmap2DROS >
-plan_
-waitingTimeout_
-alpha_offset_
-betta_offset_
-carrot_angular_distance _
-carrot_distance _
-k_alpha_
-k_betta_
-k_rho_
-max_angular _z_speed_
-max_linear _x_speed_
-transform_tolerance _
...
-goalMarkerPublisher_
-nh_
-waitingStamp_
-tf_
-currentPoseIndex_
-goalReached_
-waiting_
-name_
-costmapRos_
cl_move_base_z::forward _local_planner::ForwardLocal Planner
- yaw_goal_tolerance_
- xy_goal_tolerance_
+ ForwardLocalPlanner()
+ ~ForwardLocalPlanner()
+ configure()
+ activate()
+ deactivate()
+ cleanup()
+ setPlan()
+ computeVelocityCommands()
+ isGoalReached()
+ setSpeedLimit()
- updateParameters()
- publishGoalMarker()
- generateTrajectory()
- computeNewPositions()