```
nav2 core::Controller
cl move base z::pure
 spinning local planner
 ::PureSpinningLocalPlanner
- nh
- name

    costmapRos

- goalMarkerPublisher
- plan
- tf

    k betta

- goalReached

    currentPoseIndex

- vaw goal tolerance
- intermediate goal vaw
tolerance
- max angular z speed

    transform tolerance

+ PureSpinningLocalPlanner()
+ ~PureSpinningLocalPlanner()
+ configure()
+ activate()
+ deactivate()
+ cleanup()
+ setPlan()
+ computeVelocityCommands()
+ isGoalReached()
+ setSpeedLimit()
- updateParameters()
publishGoalMarker()
```