

cl\_nav2z::pure\_spinning  
\_local\_planner::PureSpinning  
LocalPlanner::computeVelocityCommands



```
graph LR; A["cl_nav2z::pure_spinning  
_local_planner::PureSpinning  
LocalPlanner::computeVelocityCommands"] --> B["cl_nav2z::pure_spinning  
_local_planner::PureSpinning  
LocalPlanner::updateParameters"]; B --> C["cl_nav2z::pure_spinning  
_local_planner::tryGetOrSet"]
```

The diagram illustrates a sequence of three function calls within a PureSpinningLocalPlanner. The first call, 'computeVelocityCommands', is highlighted with a grey background. It is followed by 'updateParameters' and then 'tryGetOrSet', both in white boxes. Blue arrows indicate the flow from left to right between the boxes.

cl\_nav2z::pure\_spinning  
\_local\_planner::PureSpinning  
LocalPlanner::updateParameters

cl\_nav2z::pure\_spinning  
\_local\_planner::tryGetOrSet