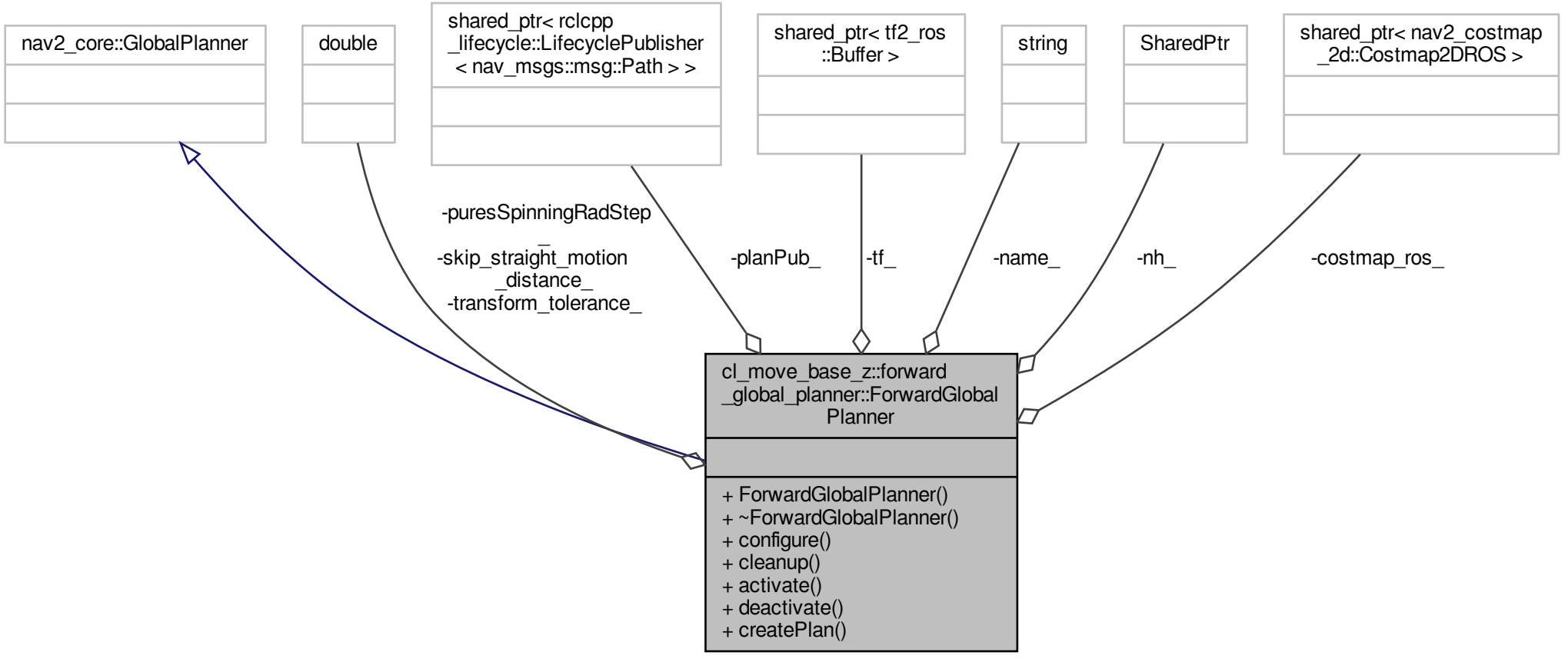
nav2_core::GlobalPlanner
double
shared_ptr< rclcpp _lifecycle::LifecyclePublisher < nav_msgs::msg::Path > >
shared_ptr< tf2_ros ::Buffer >
string
SharedPtr
shared_ptr< nav2_costmap _2d::Costmap2DROS >
-puresSpinningRadStep _
-skip_straight_motion _distance_
-transform_tolerance_
-planPub_
-tf_
-name_
-nh_
-costmap_ros_
cl_move_base_z::forward _global_planner::ForwardGlobal Planner
+ ForwardGlobalPlanner()
+ ~ForwardGlobalPlanner()
+ configure()
+ cleanup()
+ activate()
+ deactivate()
+ createPlan()