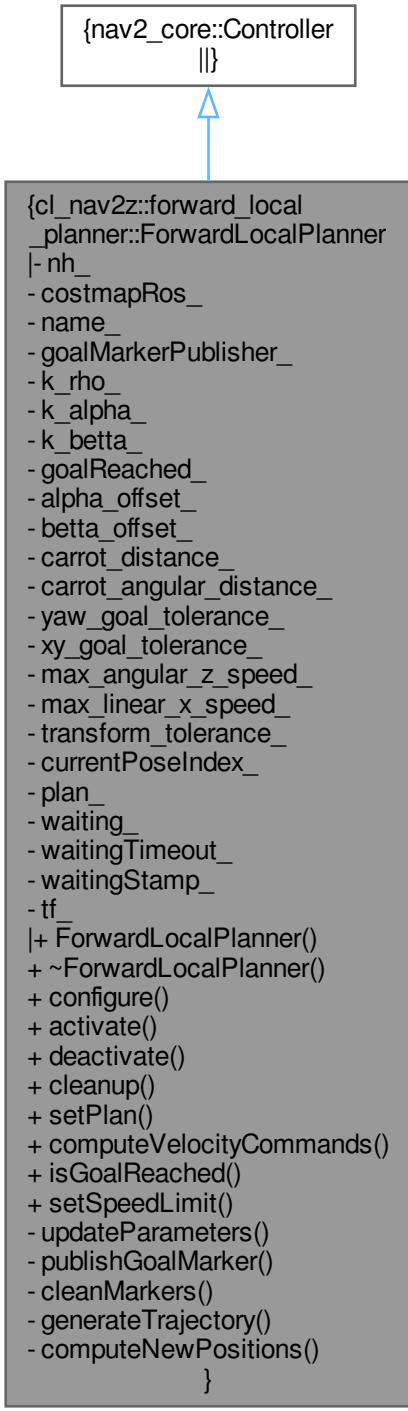
{nav2_core::Controller
||}
{cl_nav2z::forward_local
_planner::ForwardLocalPlanner
|- nh_
- costmapRos_
- name_
- goalMarkerPublisher_
- k_rho_
- k_alpha_
- k_betta_
- goalReached_
- alpha_offset_
- betta_offset_
- carrot_distance_
- carrot_angular_distance_
- yaw_goal_tolerance_
- xy_goal_tolerance_
- max_angular_z_speed_
- max_linear_x_speed_
- transform_tolerance_
- currentPoseIndex_
- plan_
- waiting_
- waitingTimeout_
- waitingStamp_
- tf_
|+ ForwardLocalPlanner()
+ ~ForwardLocalPlanner()
+ configure()
+ activate()
+ deactivate()
+ cleanup()
+ setPlan()
+ computeVelocityCommands()
+ isGoalReached()
+ setSpeedLimit()
- updateParameters()
- publishGoalMarker()
- cleanMarkers()
- generateTrajectory()
- computeNewPositions()
}