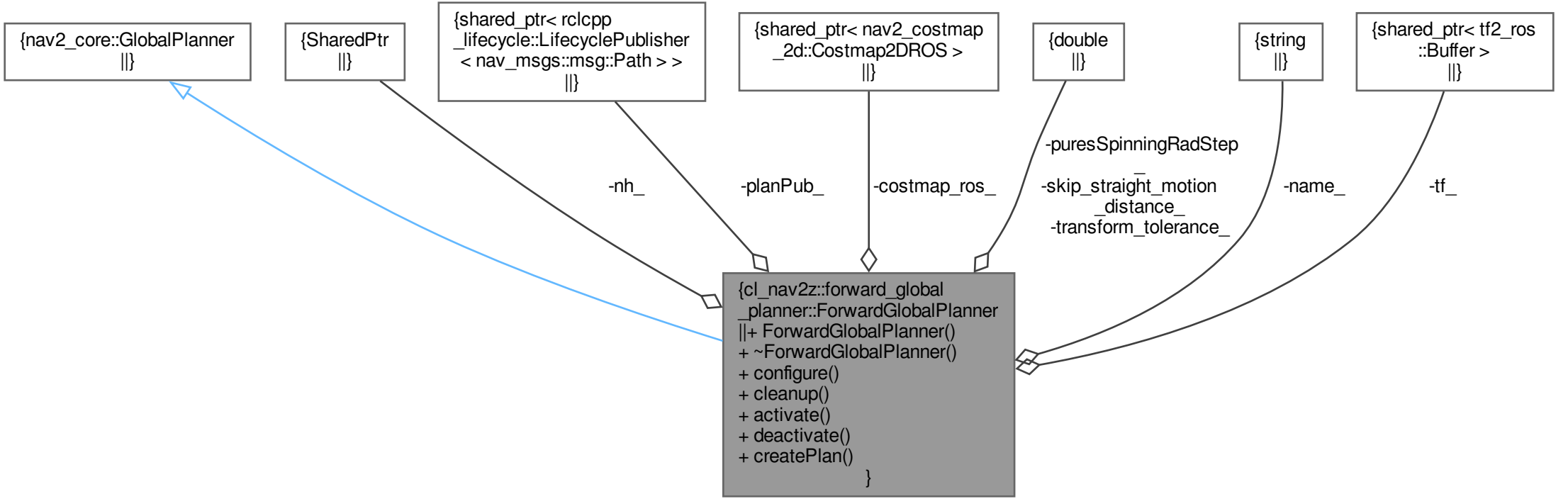
{nav2_core::GlobalPlanner
||}
{SharedPtr
||}
{shared_ptr< rclcpp
_lifecycle::LifecyclePublisher
< nav_msgs::msg::Path > >
||}
{shared_ptr< nav2_costmap
_2d::Costmap2DROS >
||}
{double
||}
{string
||}
{shared_ptr< tf2_ros
::Buffer >
||}
-nh_
-planPub_
-costmap_ros_
-puresSpinningRadStep
_
-skip_straight_motion
distance
-transform_tolerance_
-name_
-tf_
{cl_nav2z::forward_global
_planner::ForwardGlobalPlanner
||+ ForwardGlobalPlanner()
+ ~ForwardGlobalPlanner()
+ configure()
+ cleanup()
+ activate()
+ deactivate()
+ createPlan()
}