



cl_nav2z::pure_spinning
_local_planner::PureSpinning
LocalPlanner

- nh_
- name_
- costmapRos_
- goalMarkerPublisher_
- plan_
- tf_
- k_betta_
- goalReached_
- currentPoseIndex_
- yaw_goal_tolerance_
- intermediate_goal_yaw
tolerance
- max_angular_z_speed_
- transform_tolerance_
- use_shortest_angular
distance

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