```
{nav2 core::Controller
{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()
```