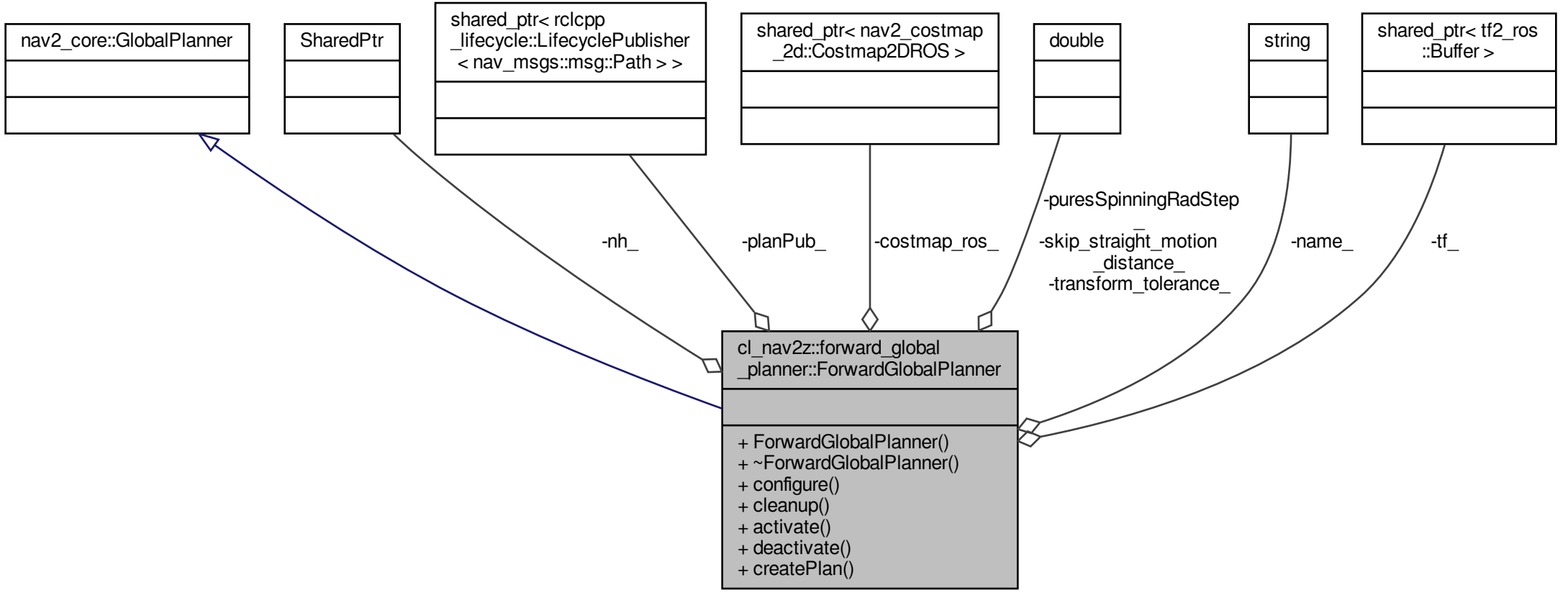
nav2_core::GlobalPlanner
SharedPtr
shared_ptr< rclcpp
_lifecycle::LifecyclePublisher
< nav_msgs::msg::Path > >
shared_ptr< nav2_costmap
_2d::Costmap2DROS >
double
string
shared_ptr< tf2_ros
::Buffer >
-nh_
-planPub_
-costmap_ros_
-puresSpinningRadStep
_
-skip_straight_motion
distance
-transform_tolerance_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