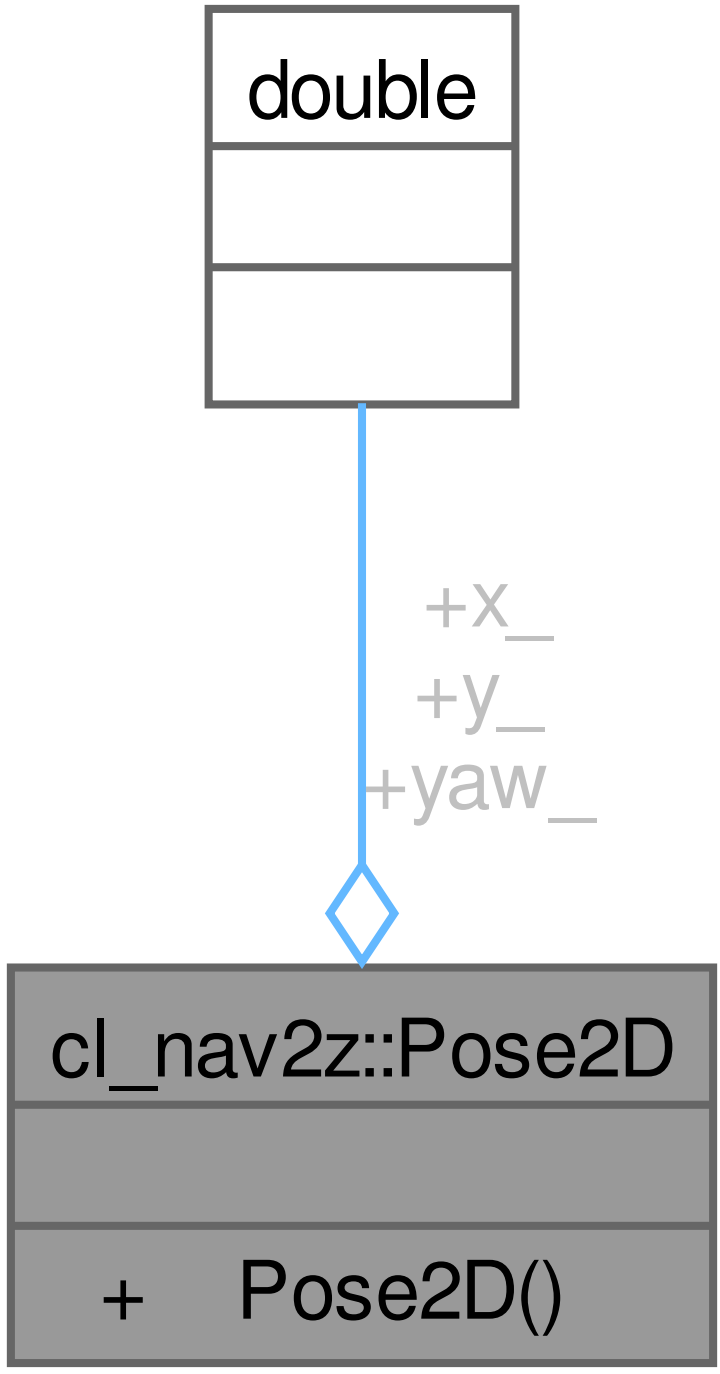
double
+x_
+y_
+yaw_
cl_nav2z::Pose2D
+ Pose2D()