```
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 vaw
tolerance
- max angular z speed
- transform tolerance
-use shortest angular
 distance
+ PureSpinningLocalPlanner()
+ ~PureSpinningLocalPlanner()
+ configure()
+ activate()
+ deactivate()
+ cleanup()
+ setPlan()
+ computeVelocityCommands()
+ isGoalReached()
+ setSpeedLimit()
- updateParameters()
publishGoalMarker()
```