

cl\_nav2z::pure\_spinning  
\_local\_planner::PureSpinning  
LocalPlanner::computeVelocityCommands



```
graph LR; A["cl_nav2z::pure_spinning  
_local_planner::PureSpinning  
LocalPlanner::computeVelocityCommands"] --> B["cl_nav2z::pure_spinning  
_local_planner::PureSpinning  
LocalPlanner::updateParameters"]; B --> C["cl_nav2z::pure_spinning  
_local_planner::tryGetOrSet"]
```

The diagram illustrates a sequence of three function calls within a PureSpinning LocalPlanner. The first call, 'computeVelocityCommands', is highlighted with a grey background. It is followed by 'updateParameters', and then 'tryGetOrSet'. Each step is contained within a rectangular box, and the boxes are connected by blue arrows pointing from left to right.

cl\_nav2z::pure\_spinning  
\_local\_planner::PureSpinning  
LocalPlanner::updateParameters

cl\_nav2z::pure\_spinning  
\_local\_planner::tryGetOrSet