

```
{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()  
  }
```