

```
{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()
```

```
}
```