## 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()