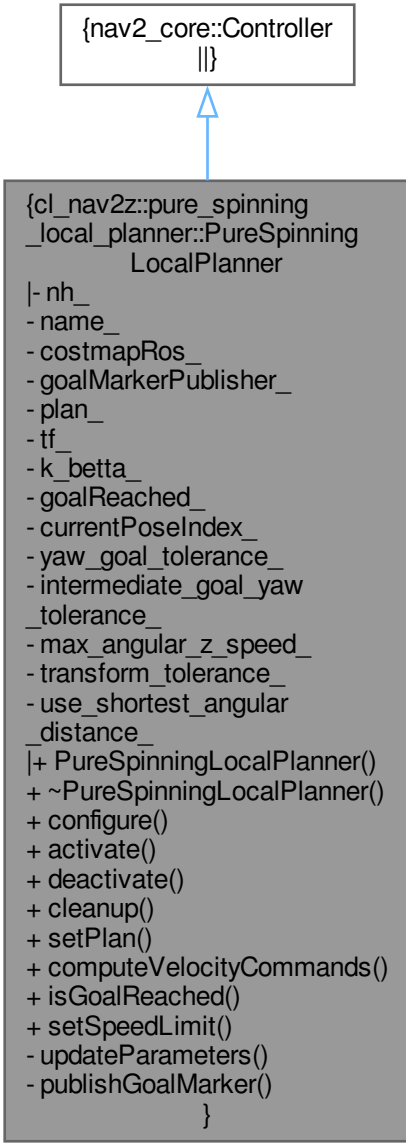
{nav2_core::Controller
||}
{cl_nav2z::pure_spinning
_local_planner::PureSpinning
LocalPlanner
|- nh_
- name_
- costmapRos_
- goalMarkerPublisher_
- plan_
- tf_
- k_betta_
- goalReached_
- currentPoseIndex_
- yaw_goal_tolerance_
- intermediate_goal_yaw
tolerance
- max_angular_z_speed_
- transform_tolerance_
- use_shortest_angular
distance
|+ PureSpinningLocalPlanner()
+ ~PureSpinningLocalPlanner()
+ configure()
+ activate()
+ deactivate()
+ cleanup()
+ setPlan()
+ computeVelocityCommands()
+ isGoalReached()
+ setSpeedLimit()
- updateParameters()
- publishGoalMarker()
}