

```
{nav_core::BaseLocalPlanner  
  ||}
```



```
{cl_move_base_z::forward  
_local_planner::ForwardLocal  
  Planner  
|- costmapRos_  
- goalMarkerPublisher_  
- k_rho_  
- k_alpha_  
- k_betta_  
- goalReached_  
- alpha_offset_  
- betta_offset_  
- carrot_distance_  
- carrot_angular_distance_  
- yaw_goal_tolerance_  
- xy_goal_tolerance_  
- max_angular_z_speed_  
- max_linear_x_speed_  
- currentPoseIndex_  
- plan_  
- waiting_  
- waitingTimeout_  
- waitingStamp_  
|+ ForwardLocalPlanner()  
+ ~ForwardLocalPlanner()  
+ computeVelocityCommands()  
+ isGoalReached()  
+ setPlan()  
+ initialize()  
+ initialize()  
+ initialize()  
- publishGoalMarker()  
- generateTrajectory()  
- computeNewPositions()  
  }
```