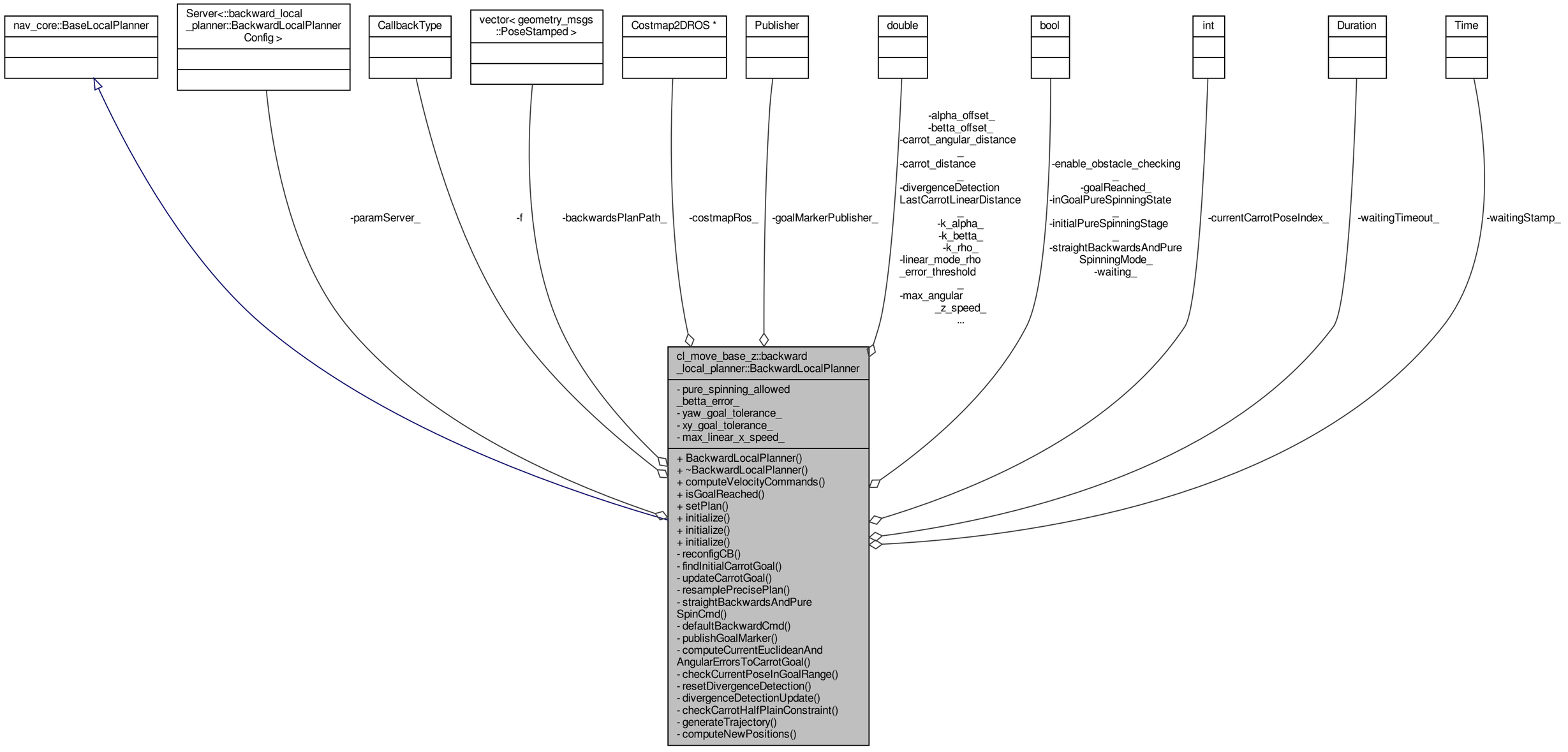
nav_core::BaseLocalPlanner
Server<::backward_local_planner::BackwardLocalPlannerConfig>
CallbackType
vector< geometry_msgs::PoseStamped >
Costmap2DROS *
Publisher
double
bool
int
Duration
Time
-paramServer_
-f
-backwardsPlanPath_
-costmapRos_
-goalMarkerPublisher_
-alpha_offset_
-betta_offset_
-carrot_angular_distance_
-carrot_distance_
-divergenceDetectionLastCarrotLinearDistance_
-k_alpha_
-k_betta_
-k_rho_
-linear_mode_rho_error_threshold_
-max_angular_z_speed_
...
-enable_obstacle_checking_
-goalReached_
-inGoalPureSpinningState_
-initialPureSpinningStage_
-straightBackwardsAndPureSpinningMode_
-waiting_
-currentCarrotPoseIndex_
-waitingTimeout_
-waitingStamp_
cl_move_base_z::backward_local_planner::BackwardLocalPlanner
- pure_spinning_allowed_betta_error_
- yaw_goal_tolerance_
- xy_goal_tolerance_
- max_linear_x_speed_
+ BackwardLocalPlanner()
+ ~BackwardLocalPlanner()
+ computeVelocityCommands()
+ isGoalReached()
+ setPlan()
+ initialize()
+ initialize()
+ initialize()
- reconfigCB()
- findInitialCarrotGoal()
- updateCarrotGoal()
- resamplePrecisePlan()
- straightBackwardsAndPureSpinCmd()
- defaultBackwardCmd()
- publishGoalMarker()
- computeCurrentEuclideanAndAngularErrorsToCarrotGoal()
- checkCurrentPoseInGoalRange()
- resetDivergenceDetection()
- divergenceDetectionUpdate()
- checkCarrotHalfPlainConstraint()
- generateTrajectory()
- computeNewPositions()