

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



```
{cl_move_base_z::pure  
_spinning_local_planner  
::PureSpinningLocalPlanner  
|- costmapRos_  
- plan_  
- paramServer_  
- k_betta_  
- goalReached_  
- currentPoseIndex_  
- yaw_goal_tolerance_  
- intermediate_goal_yaw_  
_tolerance_  
- max_angular_z_speed_  
|+ PureSpinningLocalPlanner()  
+ ~PureSpinningLocalPlanner()  
+ computeVelocityCommands()  
+ isGoalReached()  
+ setPlan()  
+ initialize()  
+ initialize()  
+ initialize()  
- reconfigCB()  
- publishGoalMarker()  
}
```