

```
{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()
  }
```