nav_core::BaseLocalPlanner
Δ
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()