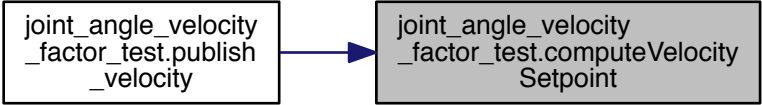


joint\_angle\_velocity  
\_factor\_test.publish  
\_velocity



```
graph LR; A["joint_angle_velocity  
_factor_test.publish  
_velocity"] --> B["joint_angle_velocity  
_factor_test.computeVelocity  
Setpoint"]
```

The diagram illustrates a data flow between two ROS nodes. On the left, a white box represents a publisher node with the name 'joint\_angle\_velocity\_factor\_test' and the topic '\_velocity'. A blue arrow points from this box to a gray box on the right, which represents a subscriber node with the same name 'joint\_angle\_velocity\_factor\_test' and the topic 'computeVelocitySetpoint'.

joint\_angle\_velocity  
\_factor\_test.computeVelocity  
Setpoint