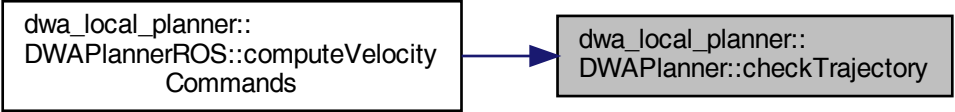


dwa\_local\_planner::  
DWAPlanerROS::computeVelocity  
Commands



```
graph LR; A["dwa_local_planner::  
DWAPlanerROS::computeVelocity  
Commands"] --> B["dwa_local_planner::  
DWAPlaner::checkTrajectory"]
```

dwa\_local\_planner::  
DWAPlaner::checkTrajectory