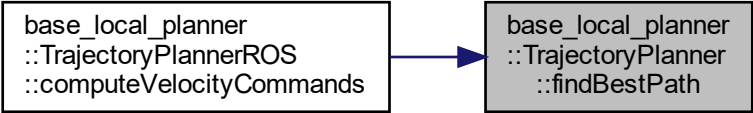


```
base_local_planner  
::TrajectoryPlannerROS  
::computeVelocityCommands
```



A diagram showing a call from a ROS node to a C++ class. A white box on the left contains the text 'base\_local\_planner', '::TrajectoryPlannerROS', and '::computeVelocityCommands'. A blue arrow points from this box to a gray box on the right. The gray box contains the text 'base\_local\_planner', '::TrajectoryPlanner', and '::findBestPath'.

```
base_local_planner  
::TrajectoryPlanner  
::findBestPath
```