

```
cl_move_base_z::forward  
_local_planner::ForwardLocal  
Planner::publishGoalMarker
```



```
graph LR; A["cl_move_base_z::forward  
_local_planner::ForwardLocal  
Planner::publishGoalMarker"] --> B["cl_move_base_z::forward  
_local_planner::optionalRobotPose"]
```

```
cl_move_base_z::forward  
_local_planner::optionalRobotPose
```