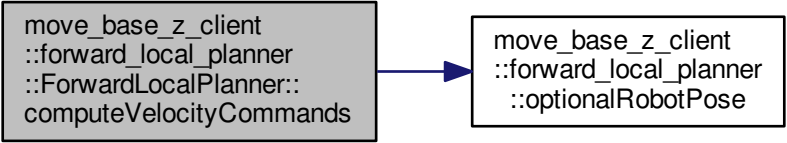


```
move_base_z_client  
::forward_local_planner  
::ForwardLocalPlanner::  
computeVelocityCommands
```



```
graph LR; A["move_base_z_client  
::forward_local_planner  
::ForwardLocalPlanner::  
computeVelocityCommands"] --> B["move_base_z_client  
::forward_local_planner  
::optionalRobotPose"]
```

```
move_base_z_client  
::forward_local_planner  
::optionalRobotPose
```