


```
cl_move_base_z::pure  
_spinning_local_planner  
::optionalRobotPose
```



```
graph LR; A["cl_move_base_z::pure  
_spinning_local_planner  
::computeVelocityCommands"] --> B["cl_move_base_z::pure  
_spinning_local_planner  
::optionalRobotPose"]
```

The diagram consists of two rectangular boxes connected by a blue arrow pointing from right to left. The right box is white with a black border and contains the text: `cl_move_base_z::pure`, `_spinning_local_planner`, `::PureSpinningLocalPlanner`, and `::computeVelocityCommands`. The left box is gray with a black border and contains the text: `cl_move_base_z::pure`, `_spinning_local_planner`, and `::optionalRobotPose`.

```
cl_move_base_z::pure  
_spinning_local_planner  
::PureSpinningLocalPlanner  
::computeVelocityCommands
```