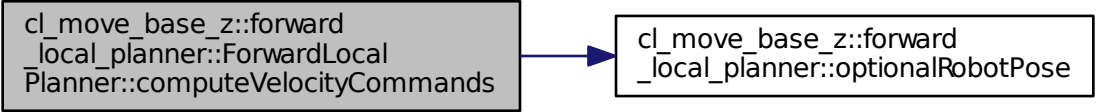


cl_move_base_z::forward
_local_planner::ForwardLocal
Planner::computeVelocityCommands



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

The diagram consists of two rectangular boxes connected by a horizontal arrow. The left box has a grey background and a black border, containing three lines of text. The right box has a white background and a black border, also containing two lines of text. A blue arrow points from the right side of the left box to the left side of the right box.

cl_move_base_z::forward
_local_planner::optionalRobotPose