

```
cl_move_base_z::forward  
_local_planner::ForwardLocal  
Planner::generateTrajectory
```



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

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