

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 is white with a black border and contains three lines of text. The right box is gray with a black border and contains two lines of text. A blue arrow points from the right side of the white box to the left side of the gray box.

cl_move_base_z::forward
_local_planner::optionalRobotPose