

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"]
```

cl_move_base_z::forward
_local_planner::optionalRobotPose