

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 blue arrow pointing from left to right. The left box has a white background and a black border, containing the text 'cl_move_base_z::forward', '_local_planner::ForwardLocal', and 'Planner::computeVelocityCommands' stacked vertically. The right box has a gray background and a black border, containing the text 'cl_move_base_z::forward' and '_local_planner::optionalRobotPose' stacked vertically.

cl_move_base_z::forward
_local_planner::optionalRobotPose