

cl\_move\_base\_z::CbNavigate  
NextWaypoint::onEntry

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graph LR; A[cl_move_base_z::CbNavigate  
NextWaypoint::onEntry] --> B[cl_move_base_z::Waypoint  
Navigator::sendNextGoal]; B --> C[cl_move_base_z::Waypoint  
Navigator::onGoalReached];
```

cl\_move\_base\_z::Waypoint  
Navigator::sendNextGoal

cl\_move\_base\_z::Waypoint  
Navigator::onGoalReached