

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 three lines of text. The right box has a light gray background and a black border, containing two lines of text. The arrow is a solid blue line with a triangular head pointing towards the right box.

cl_move_base_z::forward
_local_planner::optionalRobotPose