

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"]
```

A diagram showing a call to the `computeVelocityCommands` method of the `ForwardLocalPlanner` class. The call is made from the `cl_move_base_z::forward` function. The diagram consists of two rectangular boxes connected by a blue arrow pointing from left to right. The left box is white with a black border and contains the text `cl_move_base_z::forward`, `_local_planner::ForwardLocalPlanner::computeVelocityCommands`. The right box is gray with a black border and contains the text `cl_move_base_z::forward`, `_local_planner::optionalRobotPose`.

cl_move_base_z::forward
_local_planner::optionalRobotPose