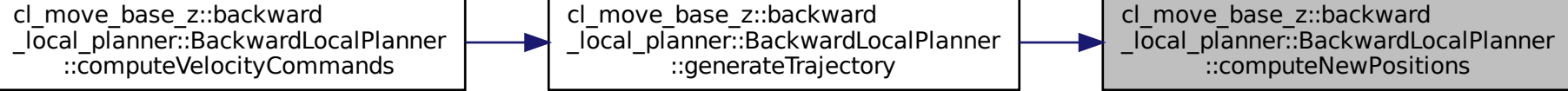


```
cl_move_base_z::backward  
_local_planner::BackwardLocalPlanner  
::computeVelocityCommands
```



```
graph LR; A[cl_move_base_z::backward  
_local_planner::BackwardLocalPlanner  
::computeVelocityCommands] --> B[cl_move_base_z::backward  
_local_planner::BackwardLocalPlanner  
::generateTrajectory]; B --> C[cl_move_base_z::backward  
_local_planner::BackwardLocalPlanner  
::computeNewPositions];
```

```
cl_move_base_z::backward  
_local_planner::BackwardLocalPlanner  
::generateTrajectory
```

```
cl_move_base_z::backward  
_local_planner::BackwardLocalPlanner  
::computeNewPositions
```