

cl\_nav2z::backward  
\_local\_planner::BackwardLocal  
Planner::activate

cl\_nav2z::backward  
\_local\_planner::BackwardLocal  
Planner::computeVelocityCommands

cl\_nav2z::backward  
\_local\_planner::BackwardLocal  
Planner::updateParameters

```
graph LR; A["cl_nav2z::backward  
_local_planner::BackwardLocal  
Planner::activate"] --> C["cl_nav2z::backward  
_local_planner::BackwardLocal  
Planner::updateParameters"]; B["cl_nav2z::backward  
_local_planner::BackwardLocal  
Planner::computeVelocityCommands"] --> C;
```

The diagram illustrates a call graph with three nodes. On the left, there are two white rectangular boxes. The top box contains the text 'cl\_nav2z::backward', '\_local\_planner::BackwardLocal', and 'Planner::activate'. The bottom box contains 'cl\_nav2z::backward', '\_local\_planner::BackwardLocal', and 'Planner::computeVelocityCommands'. On the right, there is a gray rectangular box containing 'cl\_nav2z::backward', '\_local\_planner::BackwardLocal', and 'Planner::updateParameters'. Two blue arrows point from the left boxes to the right box: one from the top box and one from the bottom box.