


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



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

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\_nav2z::backward', '\_local\_planner::BackwardLocal', and 'Planner::computeVelocityCommands'. The right box is gray with a black border and contains the text 'cl\_nav2z::backward', '\_local\_planner::BackwardLocal', and 'Planner::checkCurrentPoseInGoalRange'.

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