

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. Two source nodes on the left point to a single target node on the right. The top source node contains the text 'cl\_nav2z::backward', '\_local\_planner::BackwardLocal', and 'Planner::activate'. The bottom source node contains 'cl\_nav2z::backward', '\_local\_planner::BackwardLocal', and 'Planner::computeVelocityCommands'. The target node on the right contains 'cl\_nav2z::backward', '\_local\_planner::BackwardLocal', and 'Planner::updateParameters'. Blue arrows indicate the direction of the calls from the source nodes to the target node.