

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



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

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