

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 two source nodes on the left and one target node on the right. The top source node, labeled 'cl\_nav2z::backward \_local\_planner::BackwardLocal Planner::activate', has a blue arrow pointing to the target node. The bottom source node, labeled 'cl\_nav2z::backward \_local\_planner::BackwardLocal Planner::computeVelocityCommands', also has a blue arrow pointing to the same target node. The target node is labeled 'cl\_nav2z::backward \_local\_planner::BackwardLocal Planner::updateParameters' and is shaded gray, while the source nodes are white with black borders.