

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::generateTrajectory"]
```

A diagram showing a call from the `computeVelocityCommands` method to the `generateTrajectory` method. The left box is white with a black border, and the right box is gray with a black border. A blue arrow points from the right side of the left box to the left side of the right box.

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