

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



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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 horizontal arrow pointing from left to right. The left box has a white background and a black border, containing the text 'cl\_nav2z::backward', '\_local\_planner::BackwardLocal', and 'Planner::computeVelocityCommands' on three lines. The right box has a light gray background and a black border, containing the text 'cl\_nav2z::backward', '\_local\_planner::BackwardLocal', and 'Planner::checkCurrentPoseInGoalRange' on three lines. A dark blue arrow points from the right side of the left box to the left side of the right box.

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