


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 blue arrow pointing from left to right. The left box is white with a black border and contains the text 'cl_nav2z::backward', '_local_planner::BackwardLocal', and 'Planner::computeVelocityCommands' on three lines. The right box is gray with a black border and contains the text 'cl_nav2z::backward', '_local_planner::BackwardLocal', and 'Planner::checkCurrentPoseInGoalRange' on three lines.

cl_nav2z::backward
_local_planner::BackwardLocal
Planner::checkCurrentPoseInGoalRange