

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::checkCurrentPoseInGoalRange"]
```

The diagram illustrates a function call sequence. A white rectangular box on the left contains the text 'cl_nav2z::backward', '_local_planner::BackwardLocal', and 'Planner::computeVelocityCommands'. A blue arrow points from the right side of this box to a gray rectangular box on the right. The gray box contains the text 'cl_nav2z::backward', '_local_planner::BackwardLocal', and 'Planner::checkCurrentPoseInGoalRange'.

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