

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 three nodes. On the left, there are two white rectangular boxes with black borders. The top box contains the text 'cl_nav2z::backward', '_local_planner::BackwardLocal', and 'Planner::activate'. The bottom box contains 'cl_nav2z::backward', '_local_planner::BackwardLocal', and 'Planner::computeVelocityCommands'. On the right, there is a gray rectangular box with a black border containing the text 'cl_nav2z::backward', '_local_planner::BackwardLocal', and 'Planner::updateParameters'. Two blue arrows point from the right side of the left boxes to the left side of the gray box. The arrow from the top box points to the top of the gray box, and the arrow from the bottom box points to the middle of the gray box.