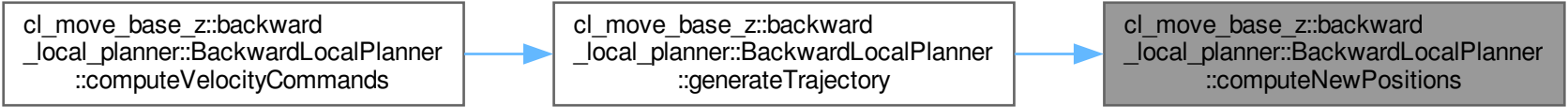


cl_move_base_z::backward
_local_planner::BackwardLocalPlanner
::computeVelocityCommands



```
graph LR; A["cl_move_base_z::backward  
_local_planner::BackwardLocalPlanner  
::computeVelocityCommands"] --> B["cl_move_base_z::backward  
_local_planner::BackwardLocalPlanner  
::generateTrajectory"]; B --> C["cl_move_base_z::backward  
_local_planner::BackwardLocalPlanner  
::computeNewPositions"]
```

The diagram illustrates a three-step process for the backward local planner. It consists of three rectangular boxes connected by blue arrows pointing from left to right. The first box (left) contains the text 'cl_move_base_z::backward', '_local_planner::BackwardLocalPlanner', and '::computeVelocityCommands'. The second box (middle) contains 'cl_move_base_z::backward', '_local_planner::BackwardLocalPlanner', and '::generateTrajectory'. The third box (right) contains 'cl_move_base_z::backward', '_local_planner::BackwardLocalPlanner', and '::computeNewPositions'. The third box is shaded gray, while the others are white with black borders.

cl_move_base_z::backward
_local_planner::BackwardLocalPlanner
::generateTrajectory

cl_move_base_z::backward
_local_planner::BackwardLocalPlanner
::computeNewPositions