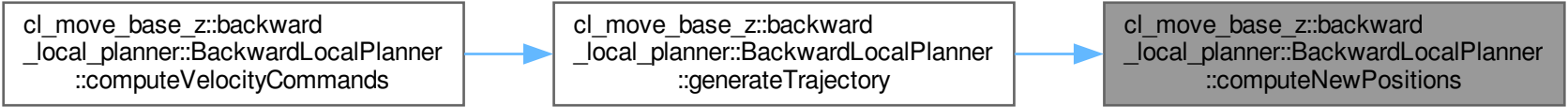


cl\_move\_base\_z::backward  
\_local\_planner::BackwardLocalPlanner  
::computeVelocityCommands



```
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 is white with a black border and contains the text 'cl\_move\_base\_z::backward', '\_local\_planner::BackwardLocalPlanner', and '::computeVelocityCommands'. A blue arrow points from this box to the second box, which is also white with a black border and contains 'cl\_move\_base\_z::backward', '\_local\_planner::BackwardLocalPlanner', and '::generateTrajectory'. Another blue arrow points from the second box to the third box, which is gray with a black border and contains 'cl\_move\_base\_z::backward', '\_local\_planner::BackwardLocalPlanner', and '::computeNewPositions'.

cl\_move\_base\_z::backward  
\_local\_planner::BackwardLocalPlanner  
::generateTrajectory

cl\_move\_base\_z::backward  
\_local\_planner::BackwardLocalPlanner  
::computeNewPositions