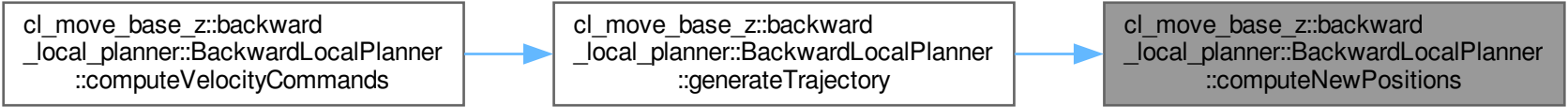


cl_move_base_z::backward
_local_planner::BackwardLocalPlanner
::computeVelocityCommands



```
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 a backward movement planner. It consists of three rectangular boxes connected by blue arrows pointing from left to right. The first box (left) 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 (middle), 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 (right), 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