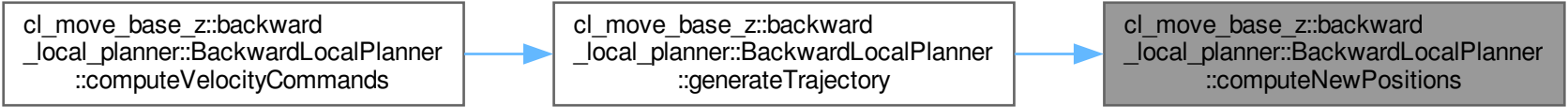


cl\_move\_base\_z::backward  
\_local\_planner::BackwardLocalPlanner  
::computeVelocityCommands



```
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"]
```

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

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