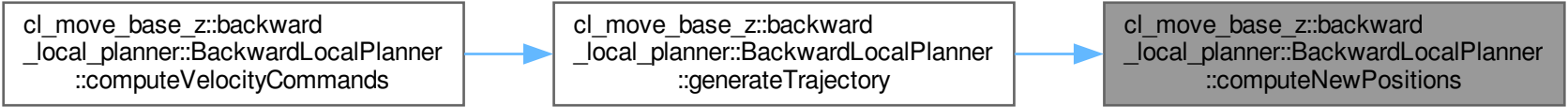


cl_move_base_z::backward
_local_planner::BackwardLocalPlanner
::computeVelocityCommands



```
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 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 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 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