

```
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  
::updateCarrotGoal"]
```

```
cl_move_base_z::backward  
_local_planner::BackwardLocalPlanner  
::updateCarrotGoal
```