

```
cl_move_base_z::backward  
_local_planner::BackwardLocalPlanner  
::findInitialCarrotGoal
```



```
graph LR; A["cl_move_base_z::backward  
_local_planner::BackwardLocalPlanner  
::findInitialCarrotGoal"] --> B["cl_move_base_z::backward  
_local_planner::BackwardLocalPlanner  
::computeCurrentEuclideanAndAngularErrors  
ToCarrotGoal"]
```

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cl_move_base_z::backward  
_local_planner::BackwardLocalPlanner  
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