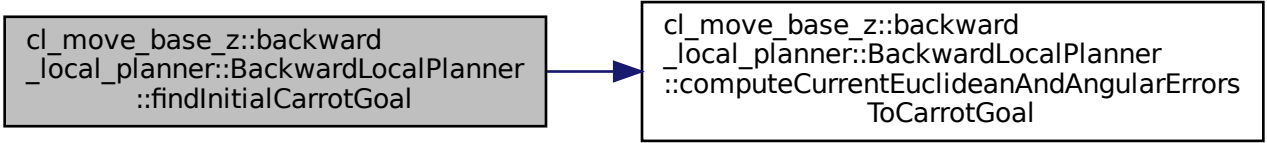


```
cl_move_base_z::backward  
_local_planner::BackwardLocalPlanner  
::findInitialCarrotGoal
```



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

The diagram consists of two rectangular boxes connected by a horizontal arrow pointing from left to right. The left box has a light gray background and a black border. It contains three lines of C++ code: `cl_move_base_z::backward`, `_local_planner::BackwardLocalPlanner`, and `::findInitialCarrotGoal`. The right box has a white background and a black border. It contains three lines of C++ code: `cl_move_base_z::backward`, `_local_planner::BackwardLocalPlanner`, and `::computeCurrentEuclideanAndAngularErrors` followed by `ToCarrotGoal` on the next line. A dark blue arrow points from the right side of the left box to the left side of the right box.

```
cl_move_base_z::backward  
_local_planner::BackwardLocalPlanner  
::computeCurrentEuclideanAndAngularErrors  
ToCarrotGoal
```