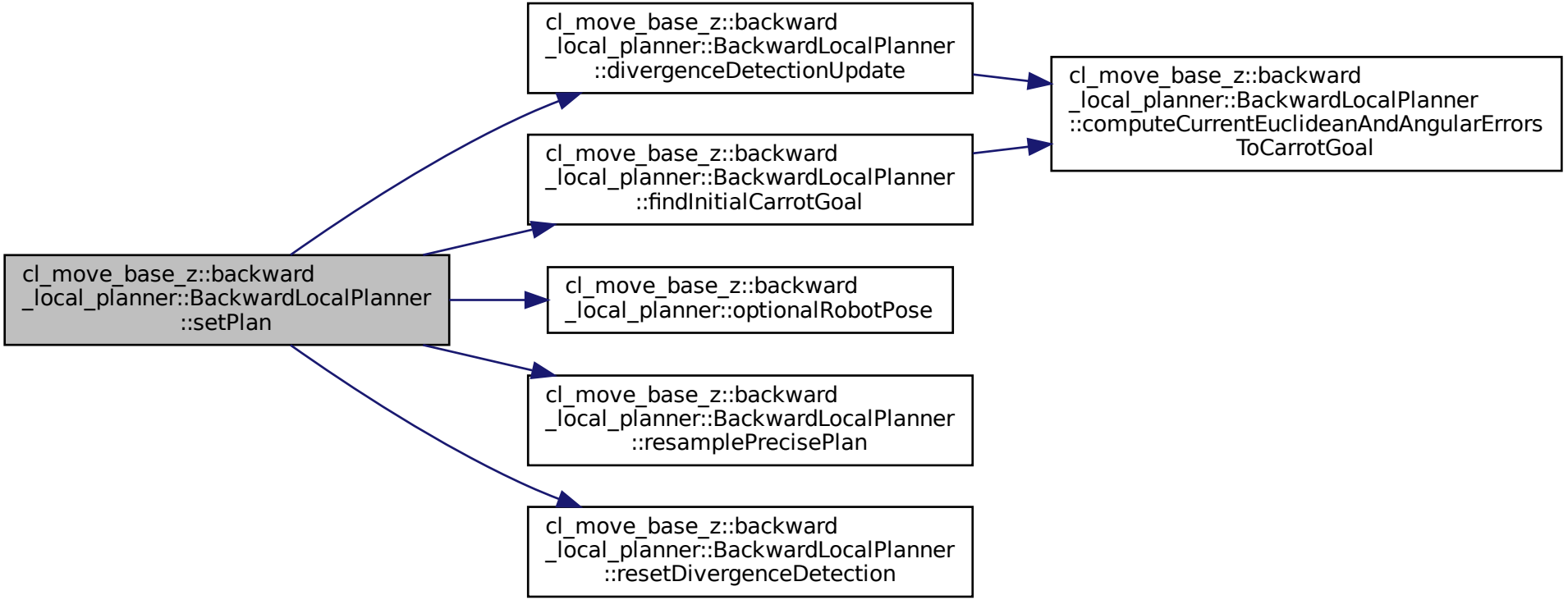
cl_move_base_z::backward
_local_planner::BackwardLocalPlanner
::setPlan
cl_move_base_z::backward
_local_planner::BackwardLocalPlanner
::divergenceDetectionUpdate
cl_move_base_z::backward
_local_planner::BackwardLocalPlanner
::computeCurrentEuclideanAndAngularErrors
ToCarrotGoal
cl_move_base_z::backward
_local_planner::BackwardLocalPlanner
::findInitialCarrotGoal
cl_move_base_z::backward
_local_planner::optionalRobotPose
cl_move_base_z::backward
_local_planner::BackwardLocalPlanner
::resamplePrecisePlan
cl_move_base_z::backward
_local_planner::BackwardLocalPlanner
::resetDivergenceDetection