

cl_nav2z::backward
_local_planner::BackwardLocal
Planner::findInitialCarrotGoal



```
graph LR; A["cl_nav2z::backward  
_local_planner::BackwardLocal  
Planner::findInitialCarrotGoal"] --> B["cl_nav2z::backward  
_local_planner::BackwardLocal  
Planner::computeCurrentEuclidean  
AndAngularErrorsToCarrotGoal"]
```

The diagram illustrates a function call sequence. A grey box on the left contains the code `cl_nav2z::backward`, `_local_planner::BackwardLocalPlanner::findInitialCarrotGoal`. A blue arrow points from this box to a white box on the right. The white box contains the code `cl_nav2z::backward`, `_local_planner::BackwardLocalPlanner::computeCurrentEuclideanAndAngularErrorsToCarrotGoal`.

cl_nav2z::backward
_local_planner::BackwardLocal
Planner::computeCurrentEuclidean
AndAngularErrorsToCarrotGoal