

cl\_nav2z::backward  
\_local\_planner::BackwardLocal  
Planner::setPlan



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

cl\_nav2z::backward  
\_local\_planner::BackwardLocal  
Planner::findInitialCarrotGoal