

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 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. The right box has a white background and a black border. The arrow is dark blue.

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