

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



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

The diagram consists of two rectangular boxes connected by a horizontal arrow. The left box has a grey background and a black border, containing three lines of text. The right box has a white background and a black border, also containing three lines of text. A blue arrow points from the right side of the left box to the left side of the right box.

cl\_nav2z::backward  
\_local\_planner::BackwardLocal  
Planner::computeCurrentEuclidean  
AndAngularErrorsToCarrotGoal