

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"]
```

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