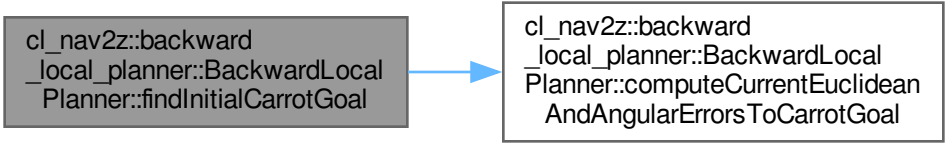
cl_nav2z::backward
_local_planner::BackwardLocal
Planner::findInitialCarrotGoal
cl_nav2z::backward
_local_planner::BackwardLocal
Planner::computeCurrentEuclidean
AndAngularErrorsToCarrotGoal