

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 illustrates a function call sequence. A grey box on the left contains the code for a backward planner's findInitialCarrotGoal method, which calls computeCurrentEuclideanAndAngularErrorsToCarrotGoal in the local planner. A blue arrow points from the first box to the second box on the right, which contains the implementation of the called method.

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