

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"]
```

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