

cl_nav2z::backward
_local_planner::BackwardLocal
Planner::setPlan



```
graph LR; A["cl_nav2z::backward  
_local_planner::BackwardLocal  
Planner::setPlan"] --> B["cl_nav2z::backward  
_local_planner::BackwardLocal  
Planner::findInitialCarrotGoal"]
```

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