cl move base z::backward _local_planner::BackwardLocalPlanner ::checkCarrotHalfPlainConstraint cl move base z::backward local planner::BackwardLocalPlanner ::checkCurrentPoseInGoalRange cl move base z::backward local planner::BackwardLocalPlanner ::defaultBackwardCmd cl move base z::backward cl move base z::backward local planner::BackwardLocalPlanner local planner::BackwardLocalPlanner ::generateTrajectory ::computeNewPositions cl move base z::backward local planner::BackwardLocalPlanner ::computeVelocityCommands cl move base z::backward local_planner::optionalRobotPose cl move base z::backward _local_planner::BackwardLocalPlanner ::publishGoalMarker cl move base z::backward _local_planner::BackwardLocalPlanner cl move base z::backward ::straightBackwardsAndPureSpinCmd local planner::BackwardLocalPlanner ::computeCurrentEuclideanAndAngularErrors ToCarrotGoal cl move base z::backward local_planner::BackwardLocalPlanner ::updateCarrotGoal cl move base z::backward local planner::BackwardLocalPlanner ::resetDivergenceDetection