```
cl move base z::backward
                                                _local_planner::BackwardLocalPlanner
                                                    ::divergenceDetectionUpdate
                                               cl move base z::backward
                                                local planner::BackwardLocalPlanner
                                                       ::findInitialCarrotGoal
cl_move_base_z::backward
                                                 cl move base z::backward
_local_planner::BackwardLocalPlanner
                                                  local planner::optionalRobotPose
              ::setPlan
                                               cl move base z::backward
                                                _local_planner::BackwardLocalPlanner
                                                       ::resamplePrecisePlan
```

cl move base z::backward

_local_planner::BackwardLocalPlanner ::resetDivergenceDetection cl_move_base_z::backward _local_planner::BackwardLocalPlanner ::computeCurrentEuclideanAndAngularErrors ToCarrotGoal