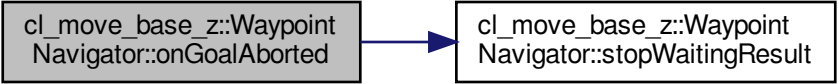


cl\_move\_base\_z::Waypoint  
Navigator::onGoalAborted



```
graph LR; A["cl_move_base_z::Waypoint  
Navigator::onGoalAborted"] --> B["cl_move_base_z::Waypoint  
Navigator::stopWaitingResult"]
```

cl\_move\_base\_z::Waypoint  
Navigator::stopWaitingResult