

cl\_nav2z::undo\_path  
\_global\_planner::UndoPathGlobal  
Planner::createPlan



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graph LR; A["cl_nav2z::undo_path  
_global_planner::UndoPathGlobal  
Planner::createPlan"] --> B["cl_nav2z::pure_spinning  
_local_planner::publishGoalMarker"]
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cl\_nav2z::pure\_spinning  
\_local\_planner::publishGoalMarker