

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